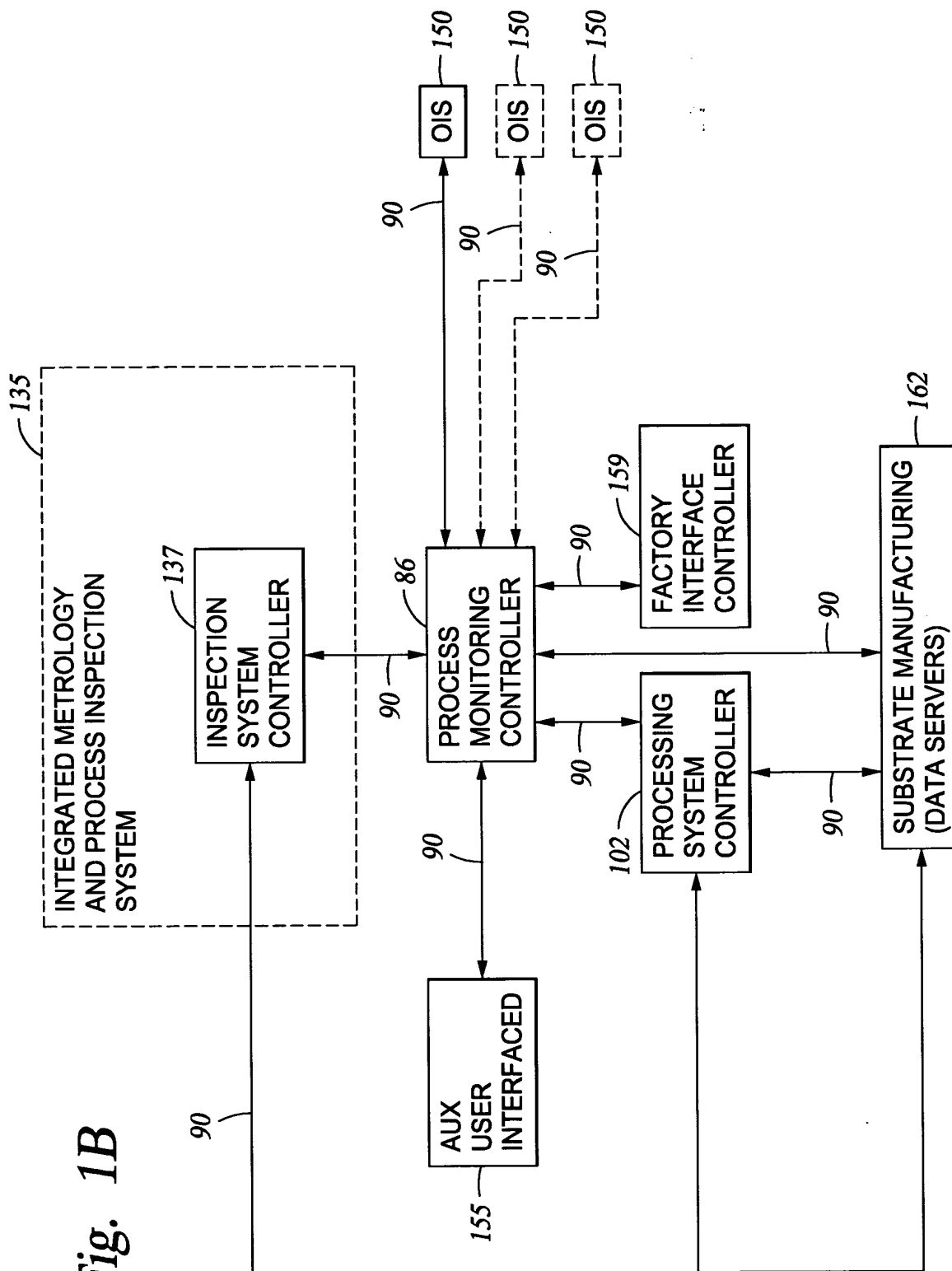


Fig. 1A

Fig. 1B



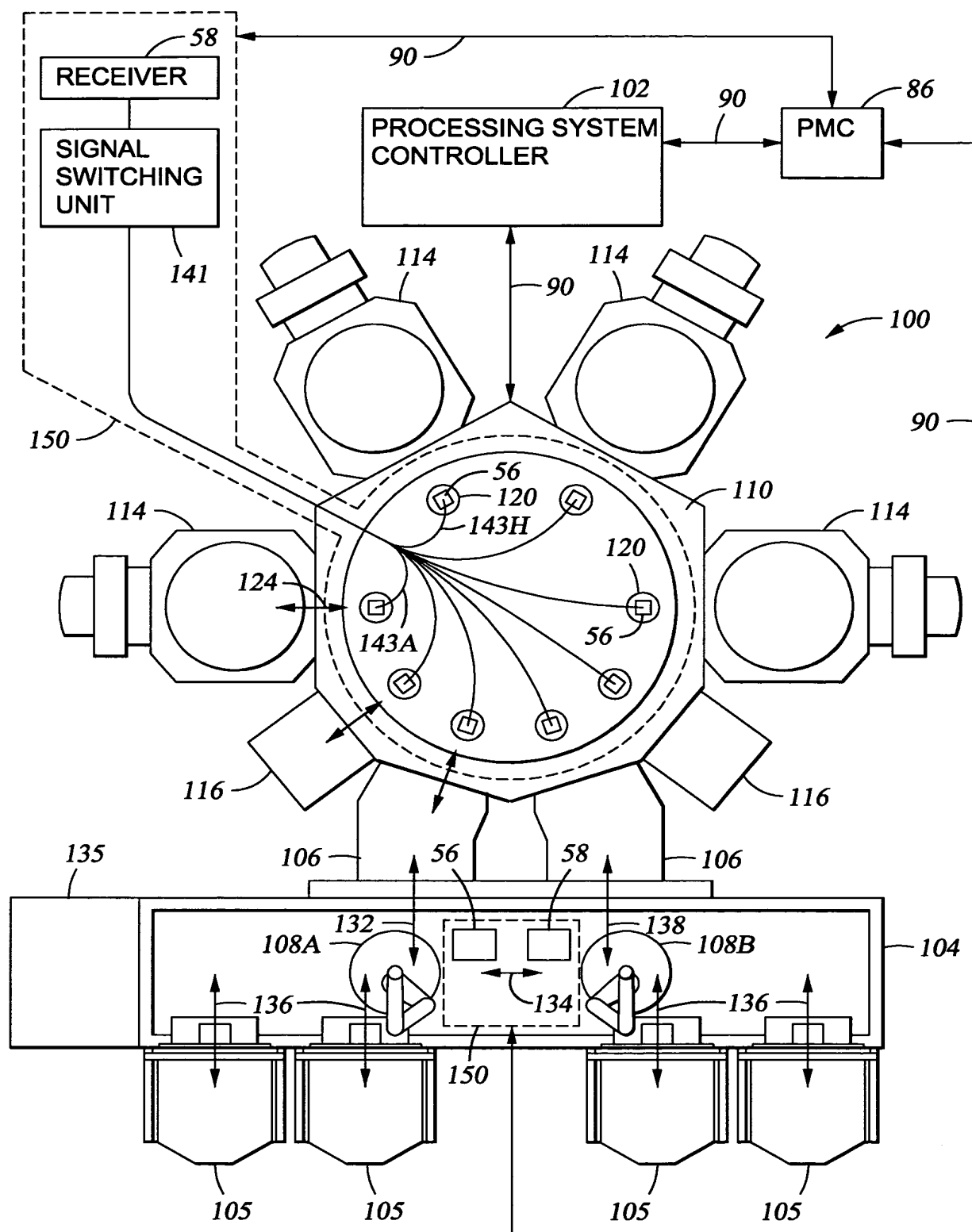


Fig. 1C

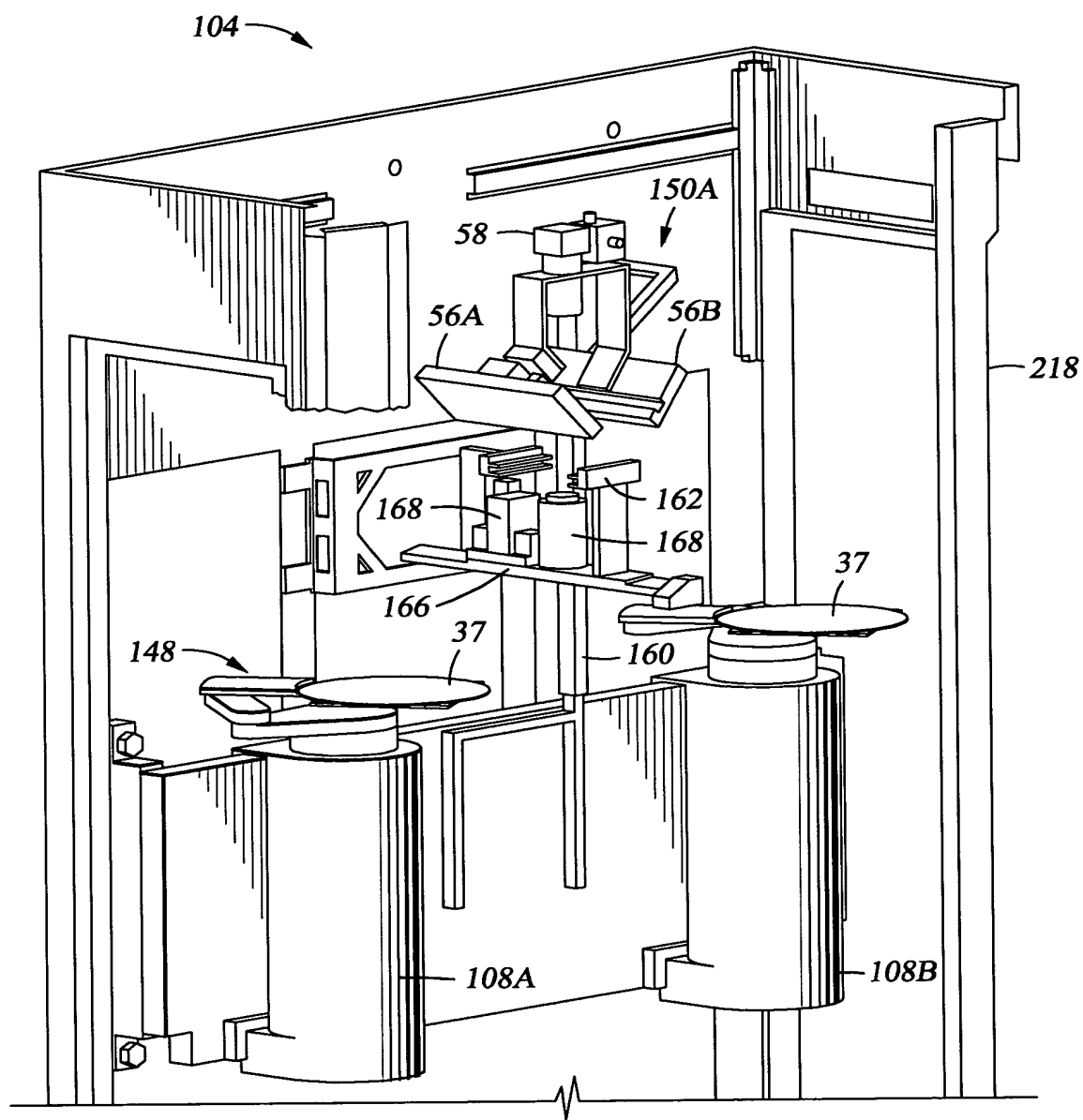


Fig. 2

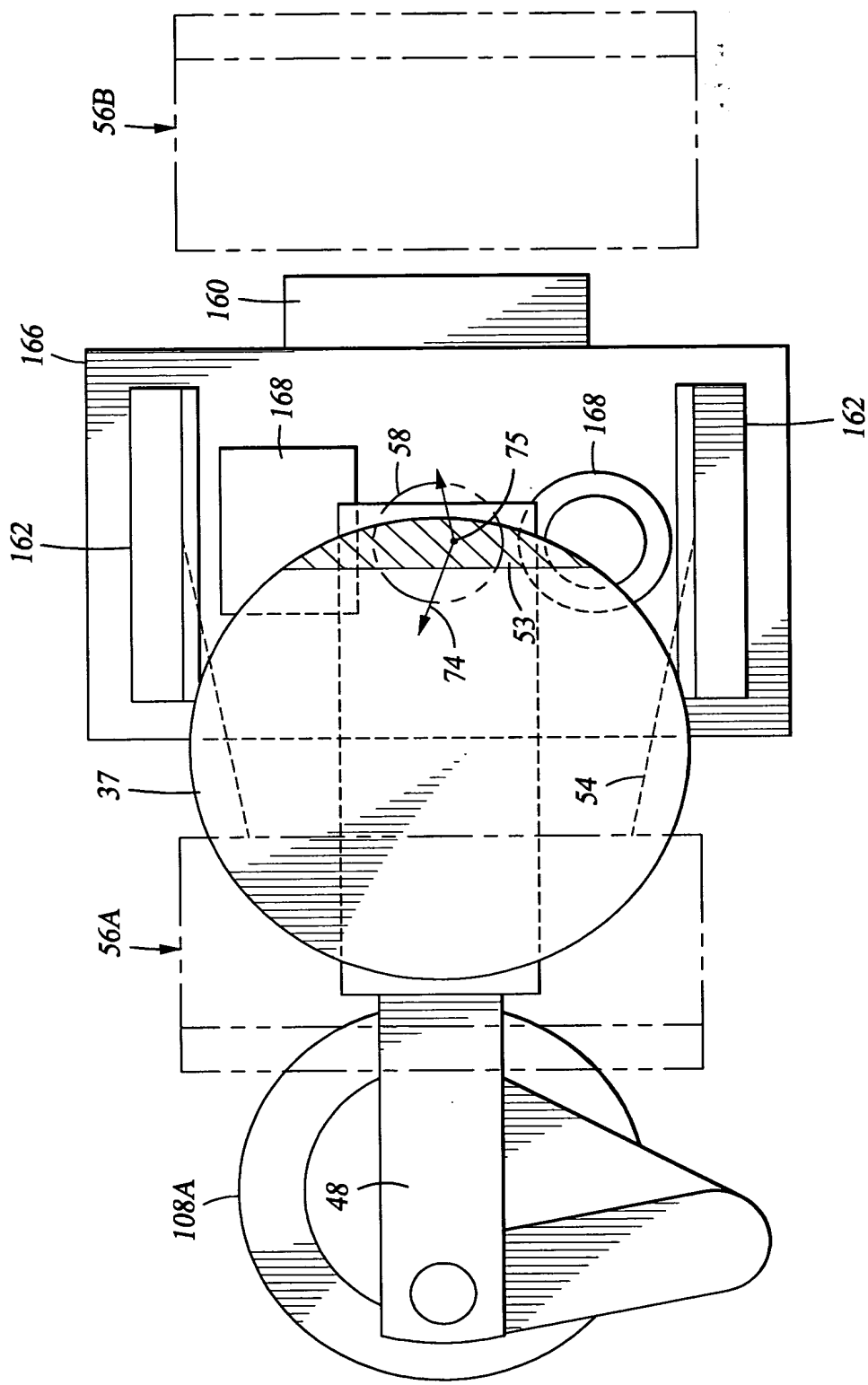


Fig. 3A

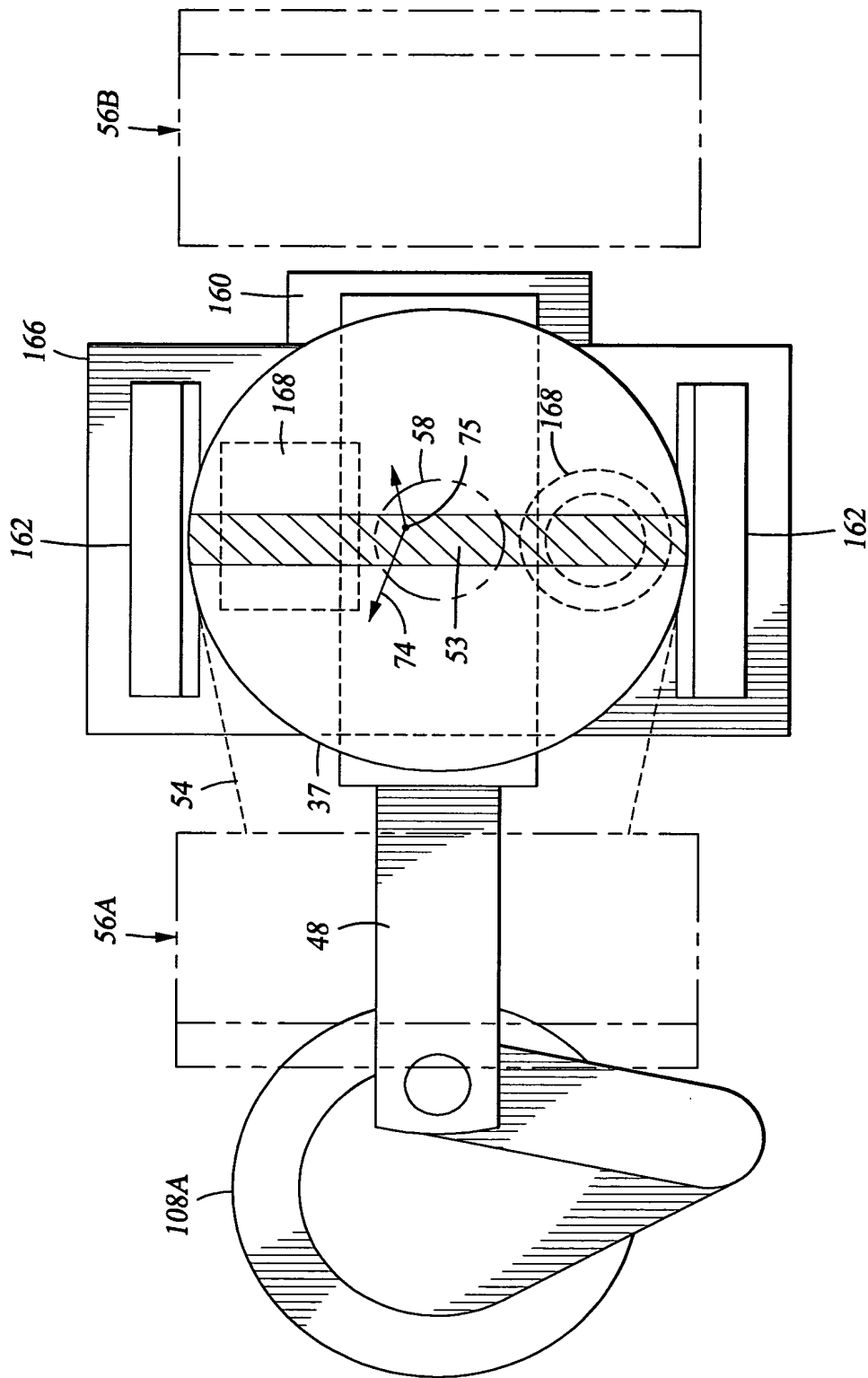


Fig. 3B

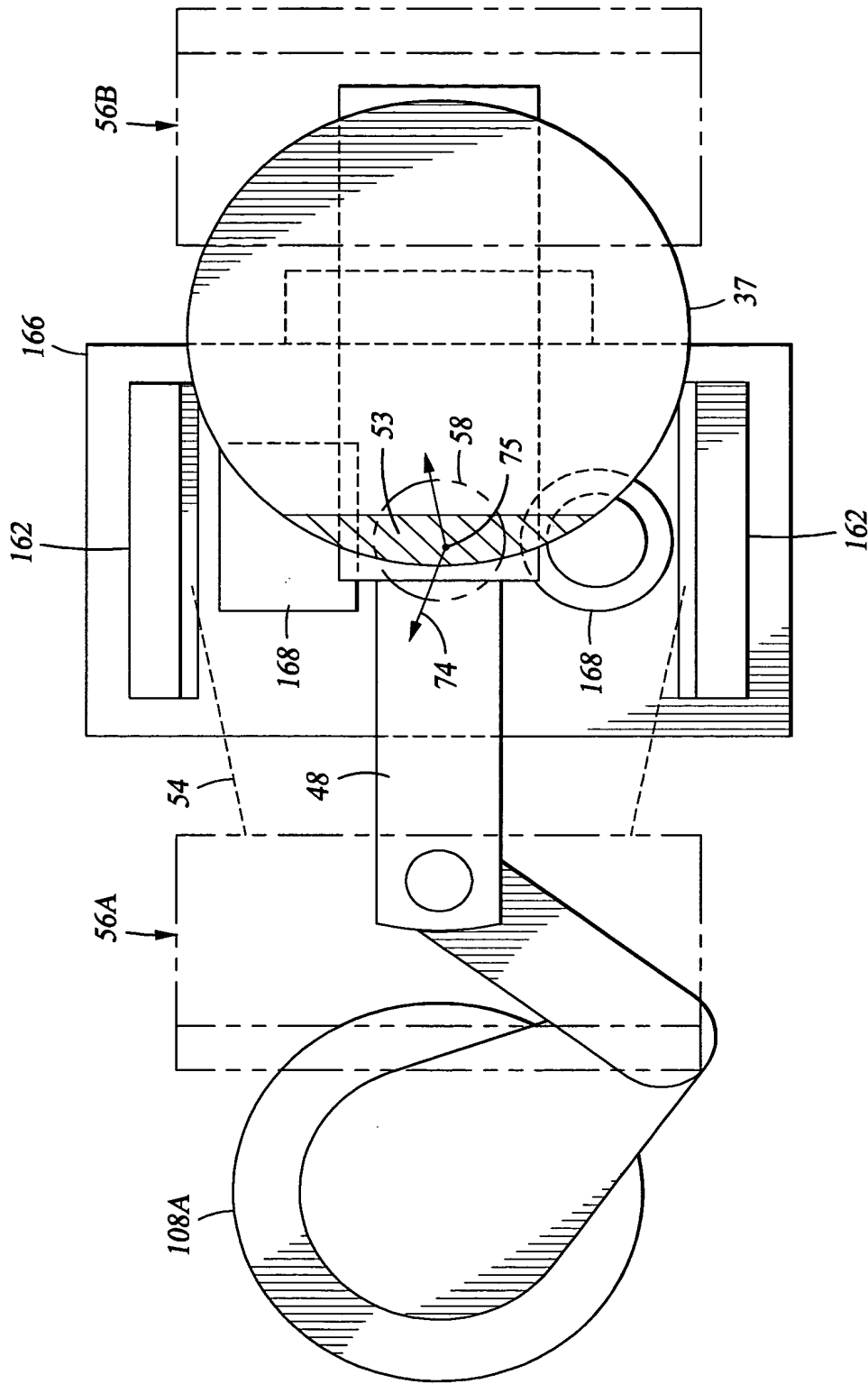


Fig. 3C

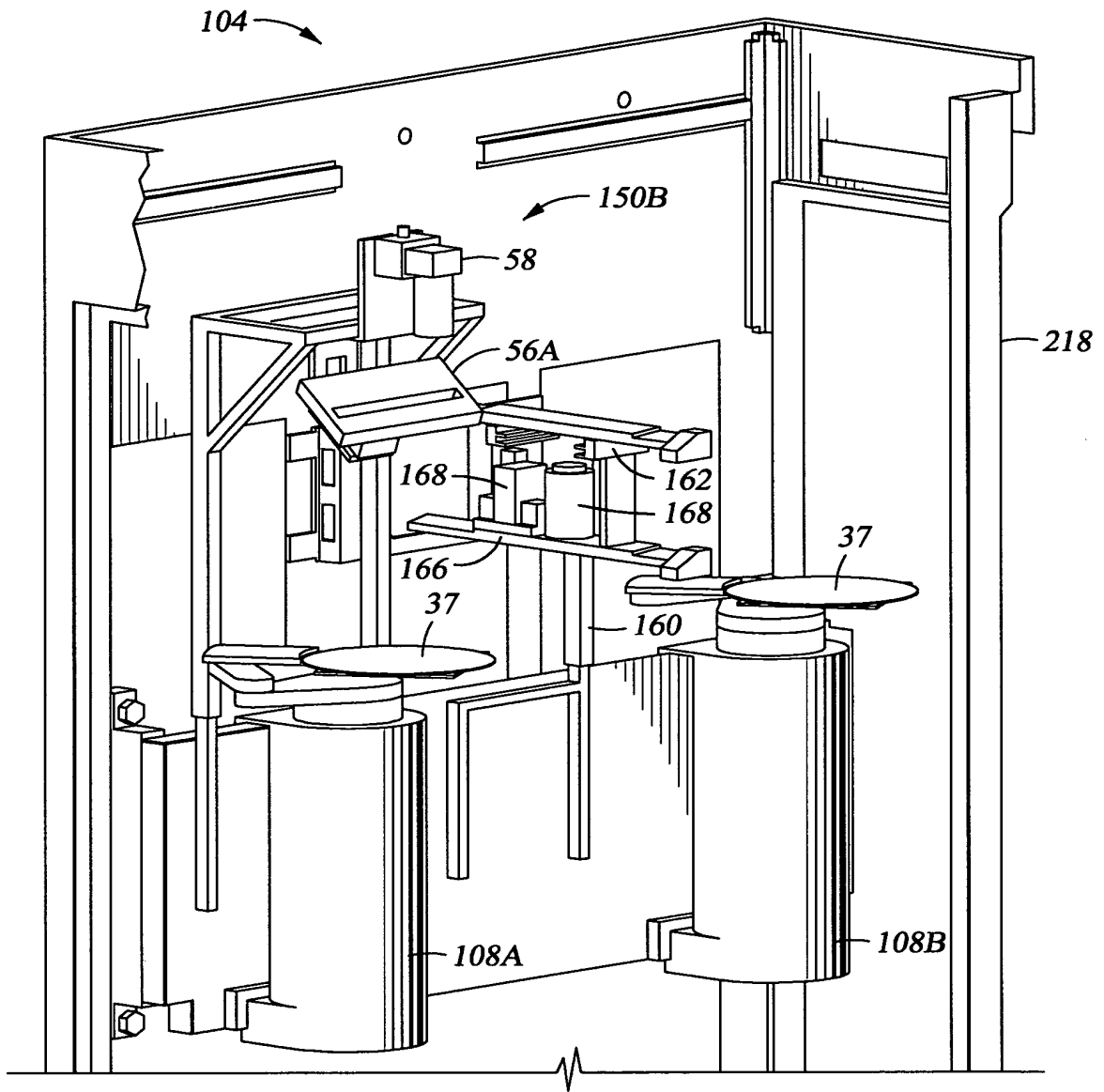


Fig. 4



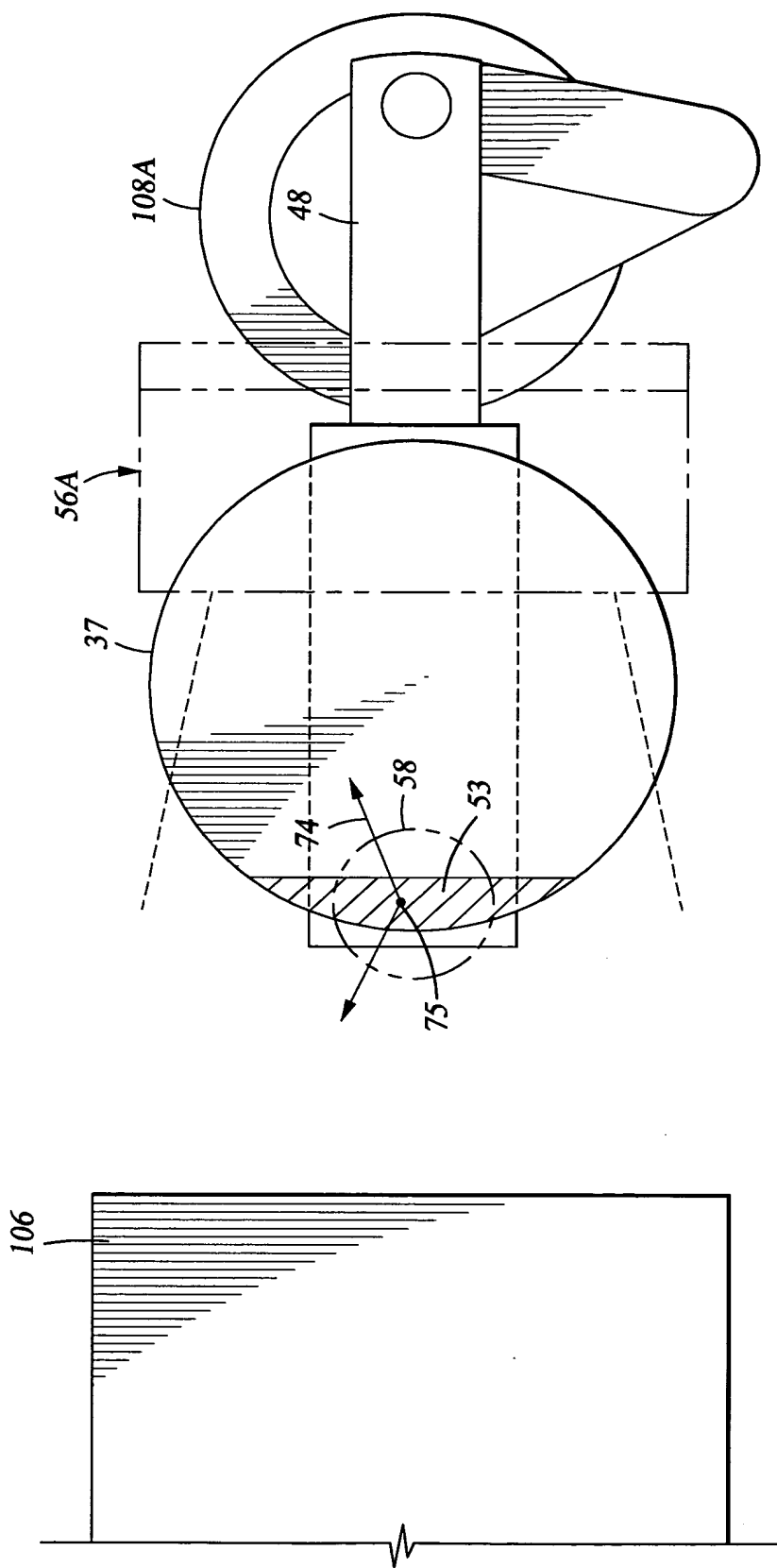


Fig. 5A

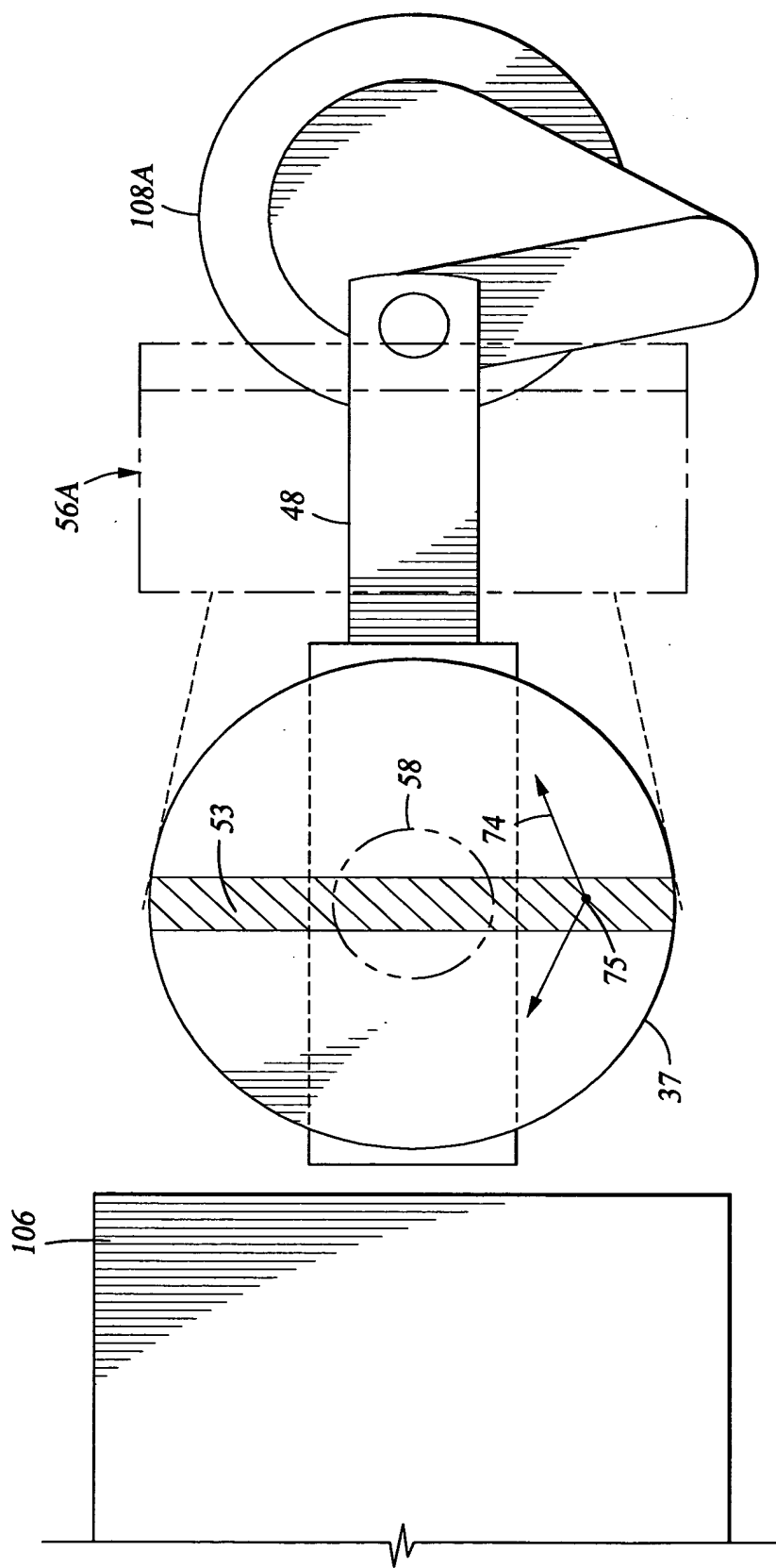


Fig. 5B

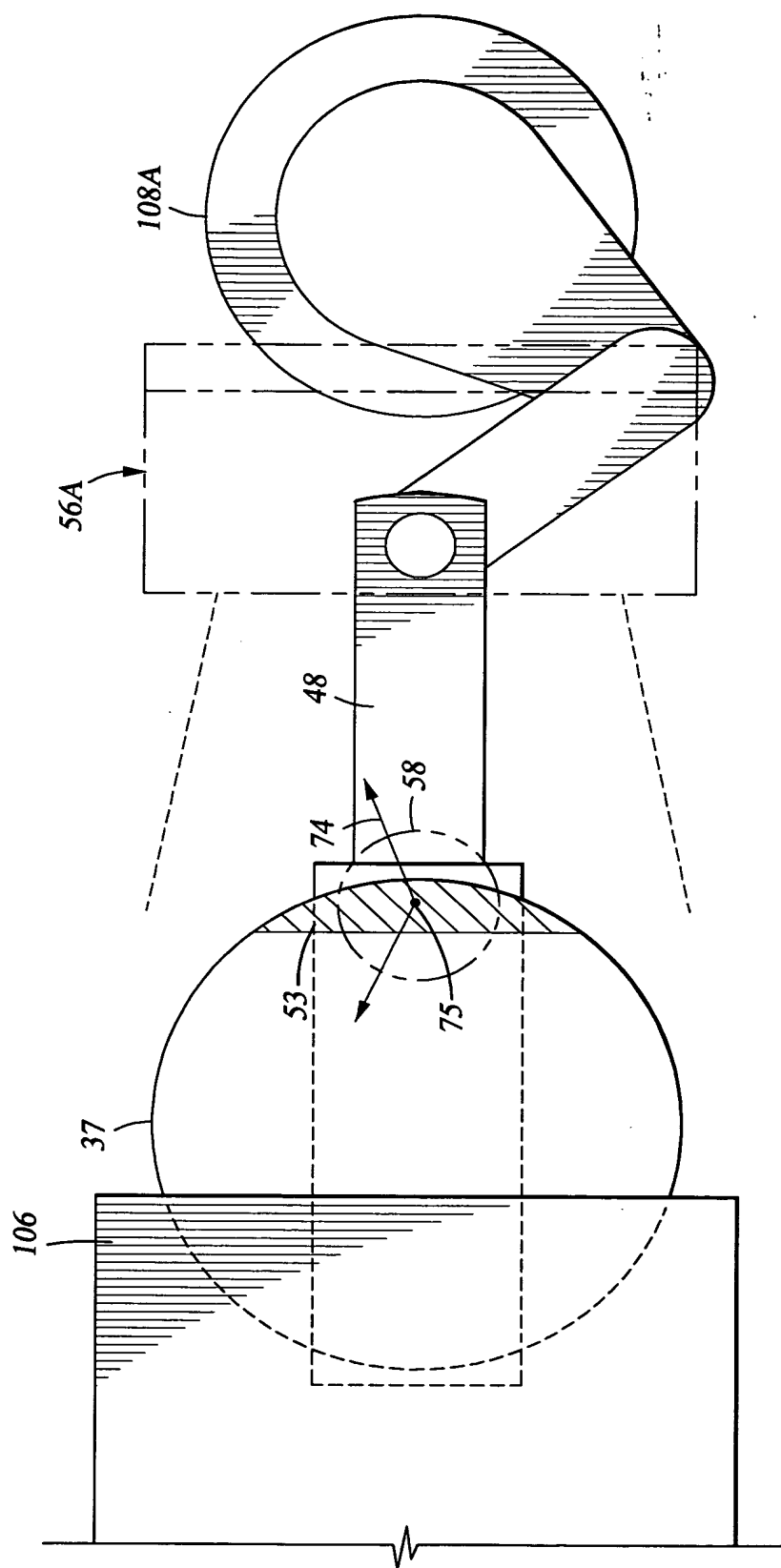
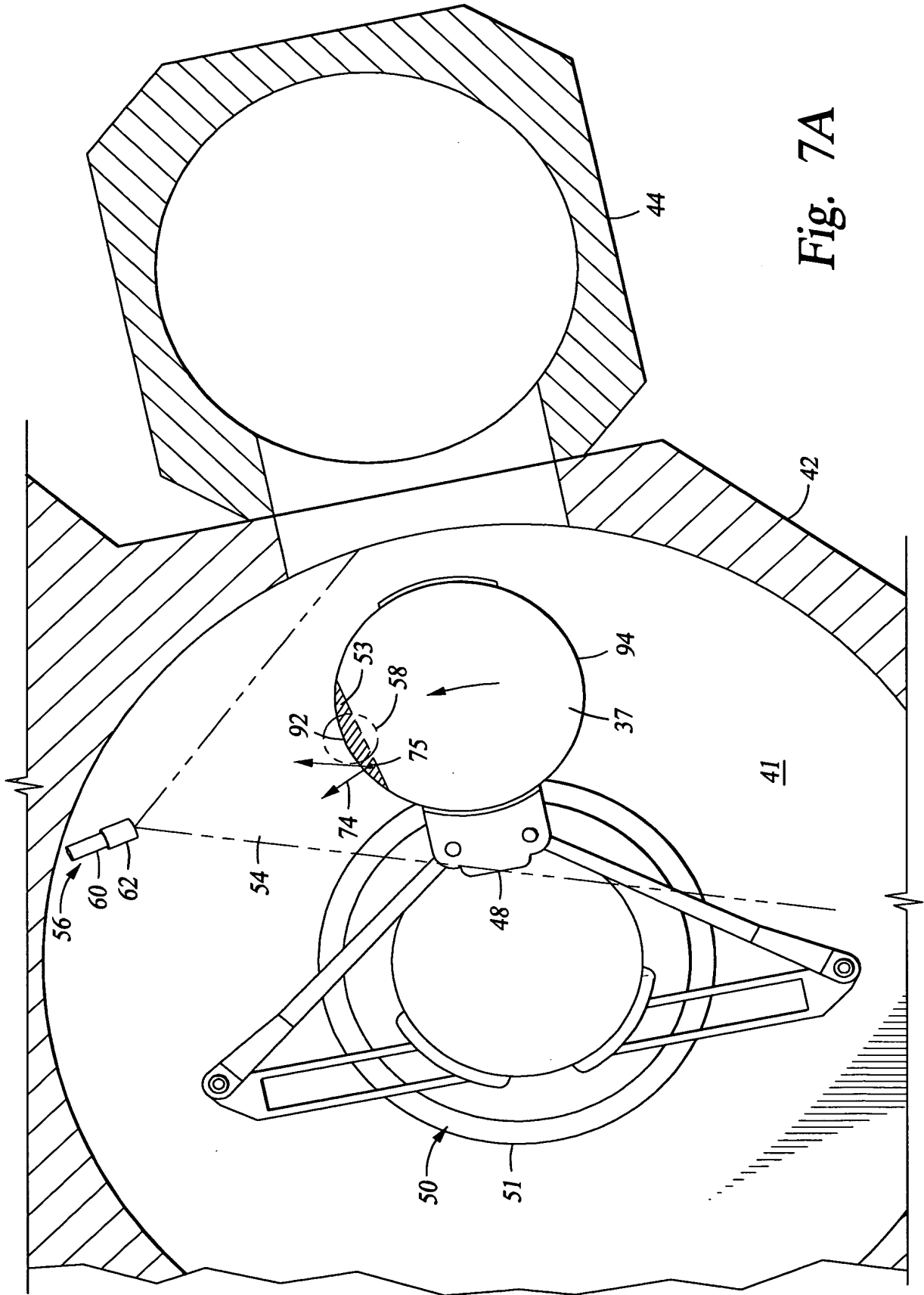


Fig. 5C

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The diagram illustrates a robotic arm assembly (50) with a base (41) and a lever arm (37). A motor (39) is connected to a gear (51) on a shaft (48). The lever arm (37) is pivoted at (75) and has a gear (53) at its end. A sensor/actuator (60) is mounted on the base, with a cable (66) connecting it to a processing system controller (102) via a PMC (62). The diagram includes various numbered components (41, 42, 44, 46, 52, 54, 56, 58, 60, 61, 64, 66, 69, 70, 72, 74, 75, 80, 82, 90, 92) and a coordinate system (X, Y, Z) at the bottom left.



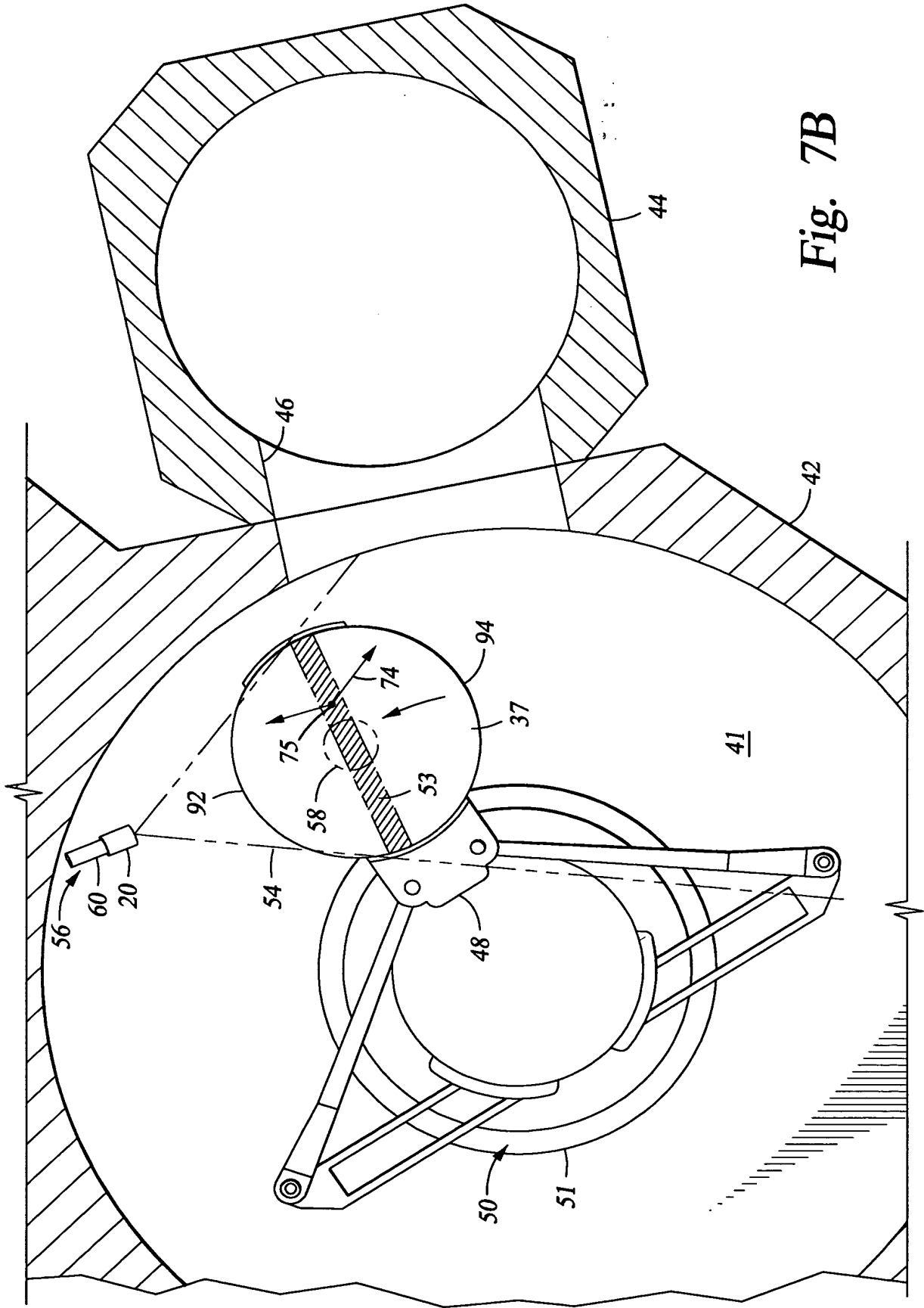


Fig. 7B

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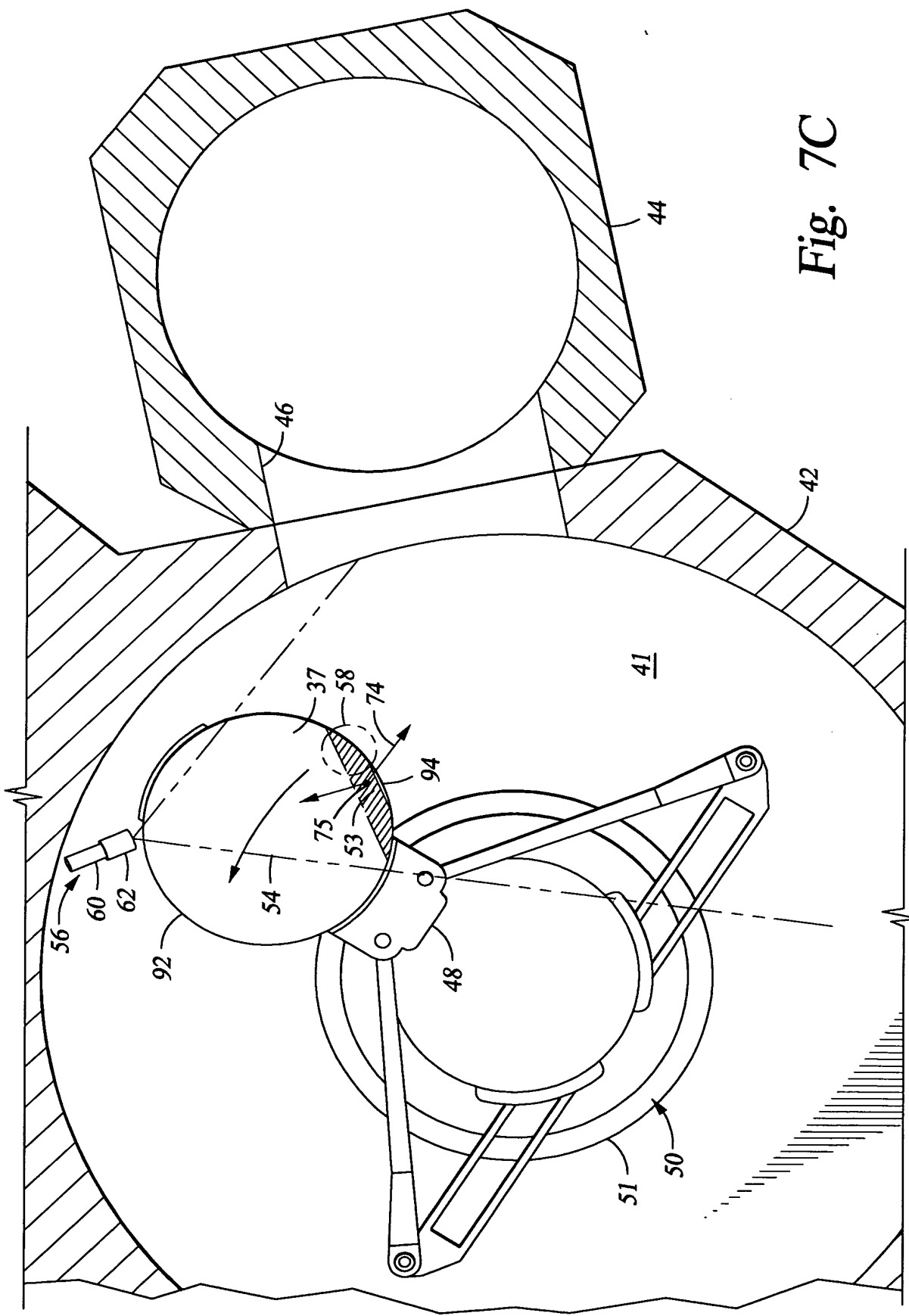


Fig. 7C

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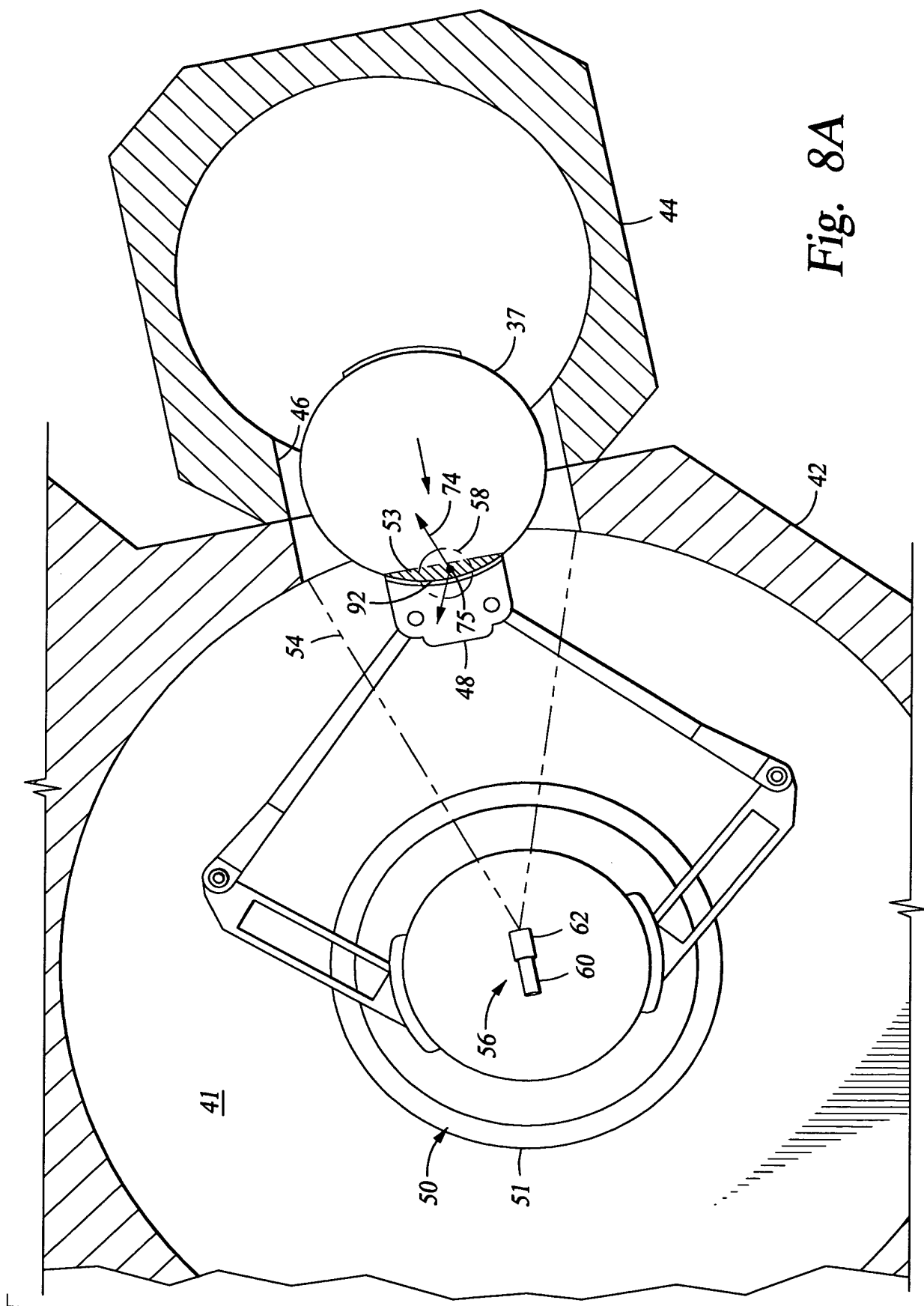
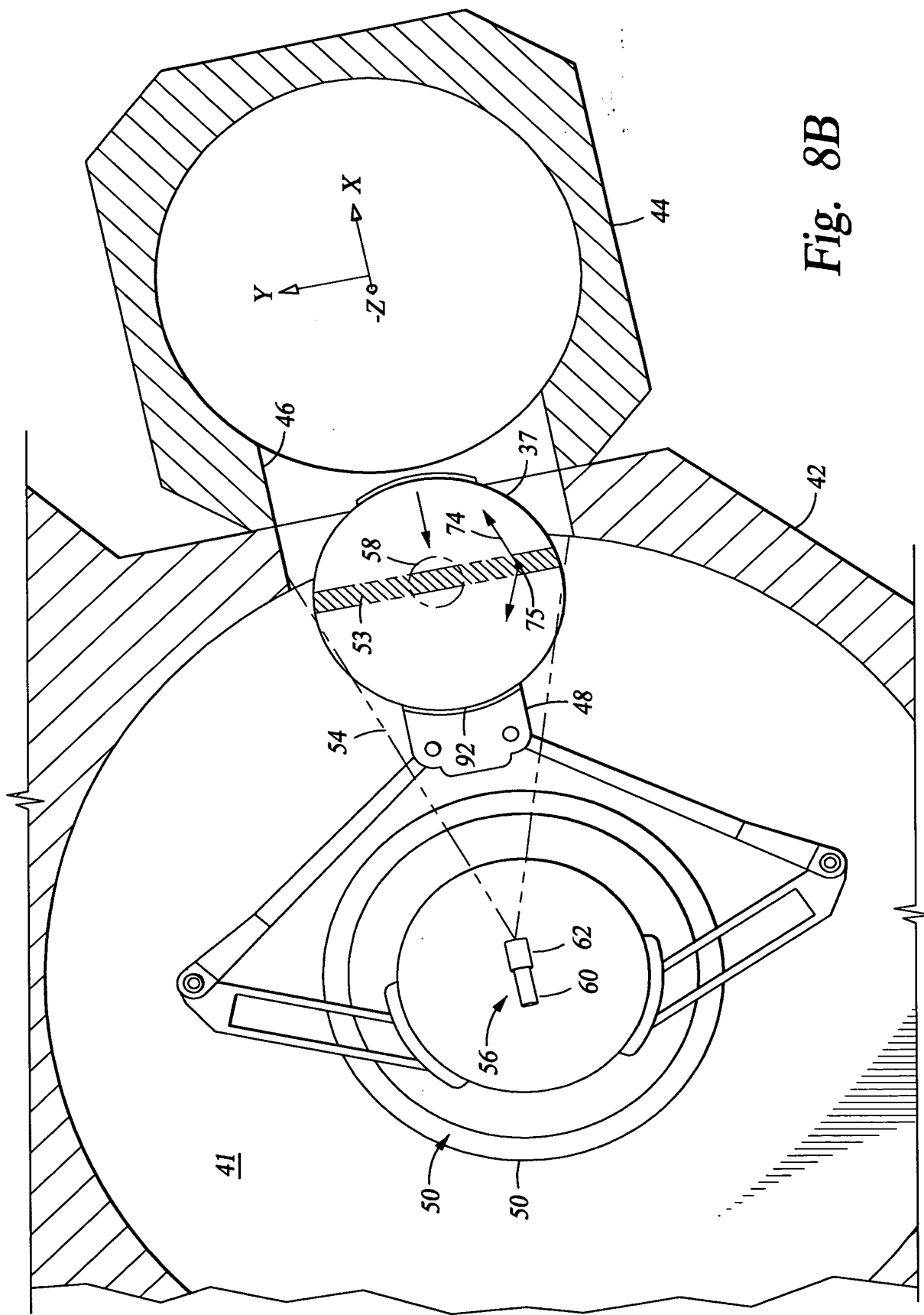


Fig. 8A





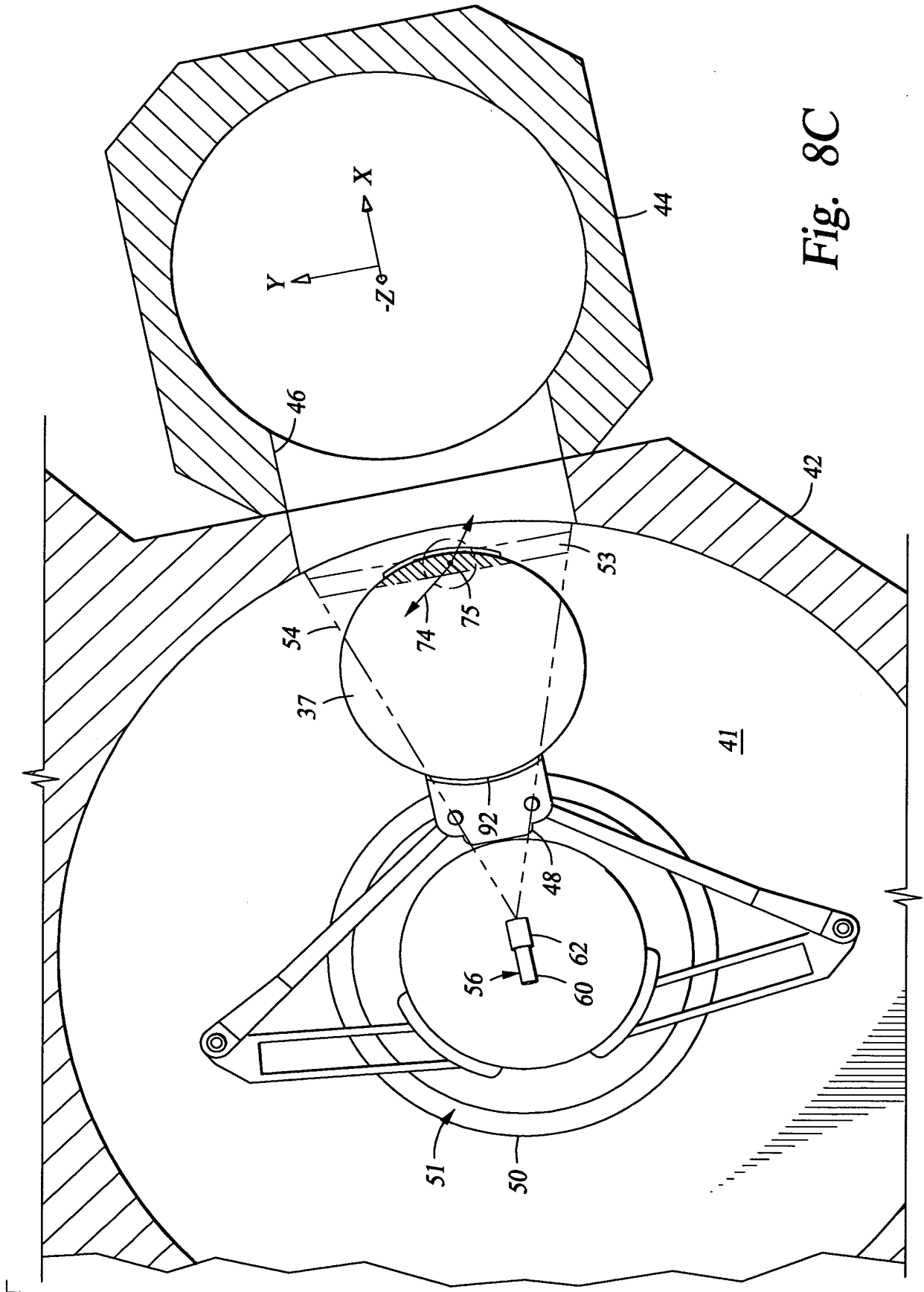


Fig. 9

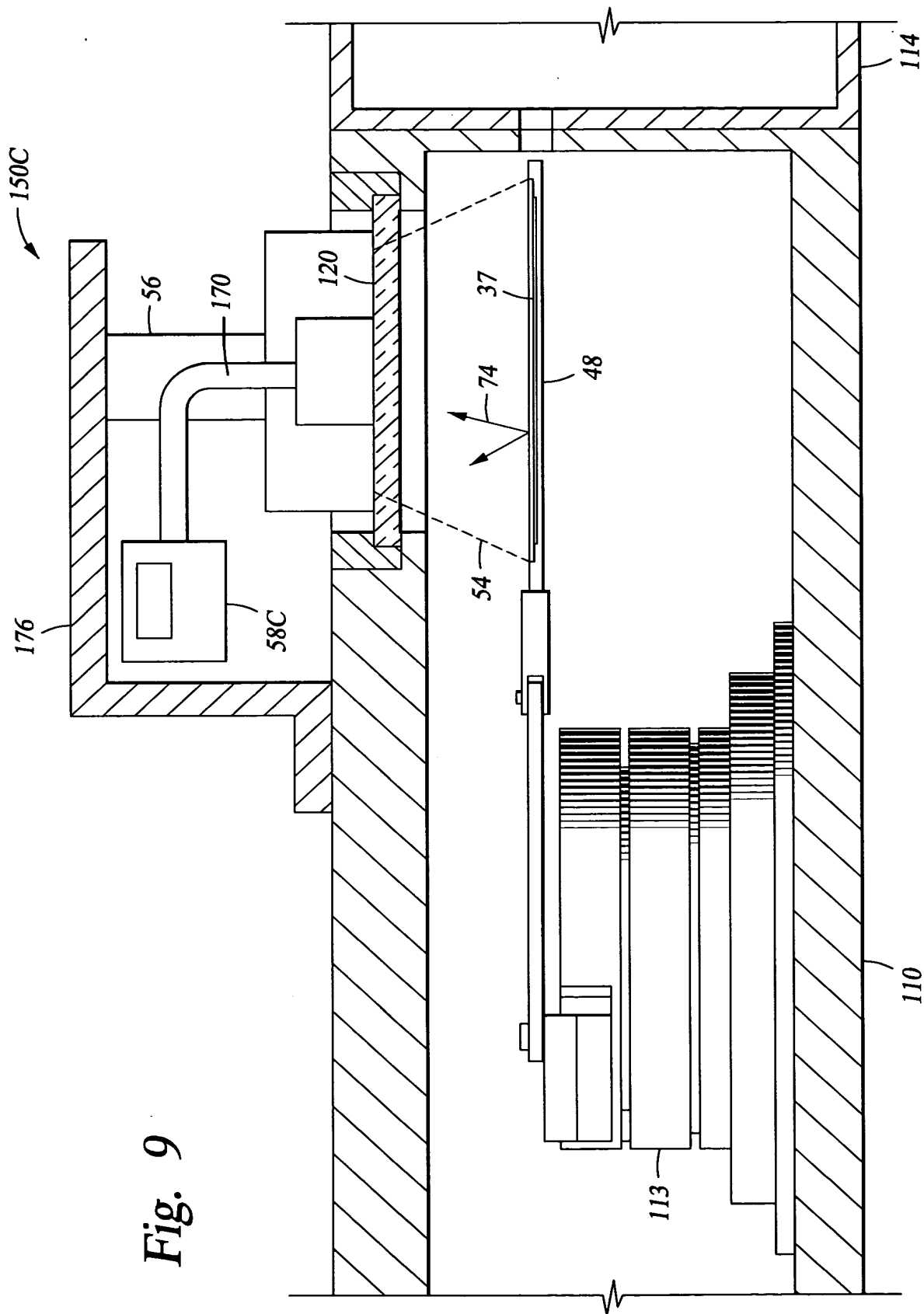
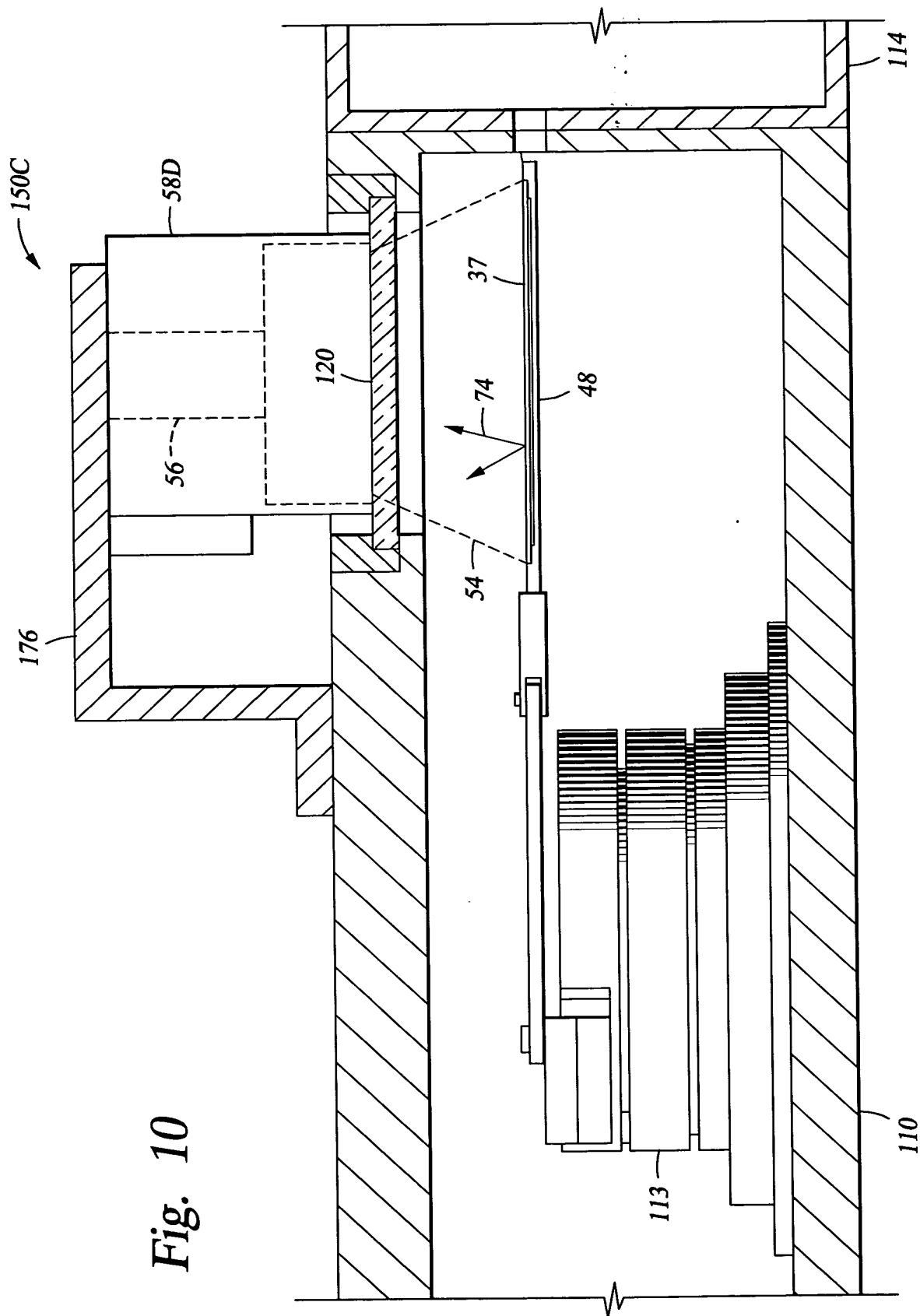


Fig. 10



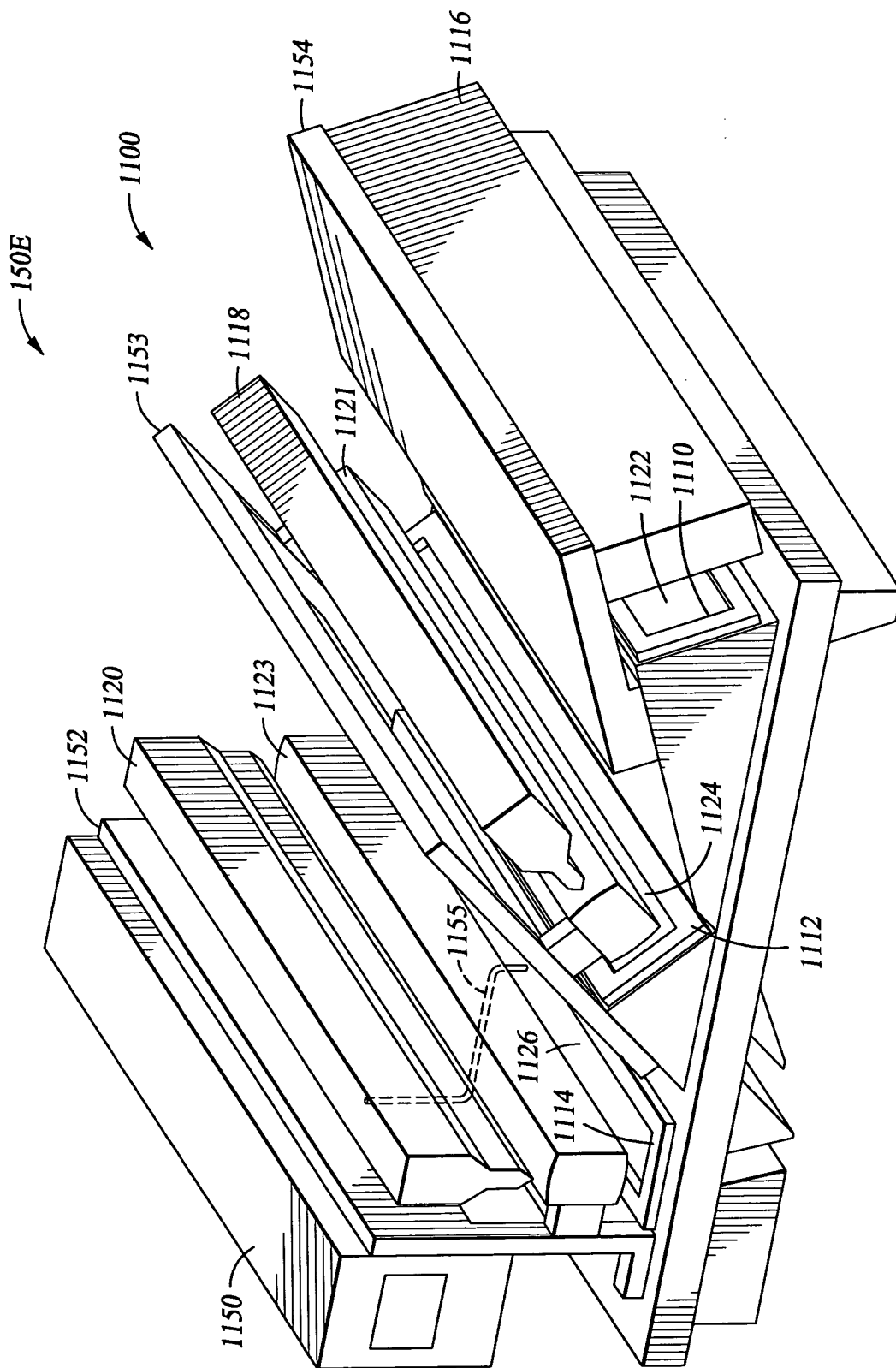


Fig. 11

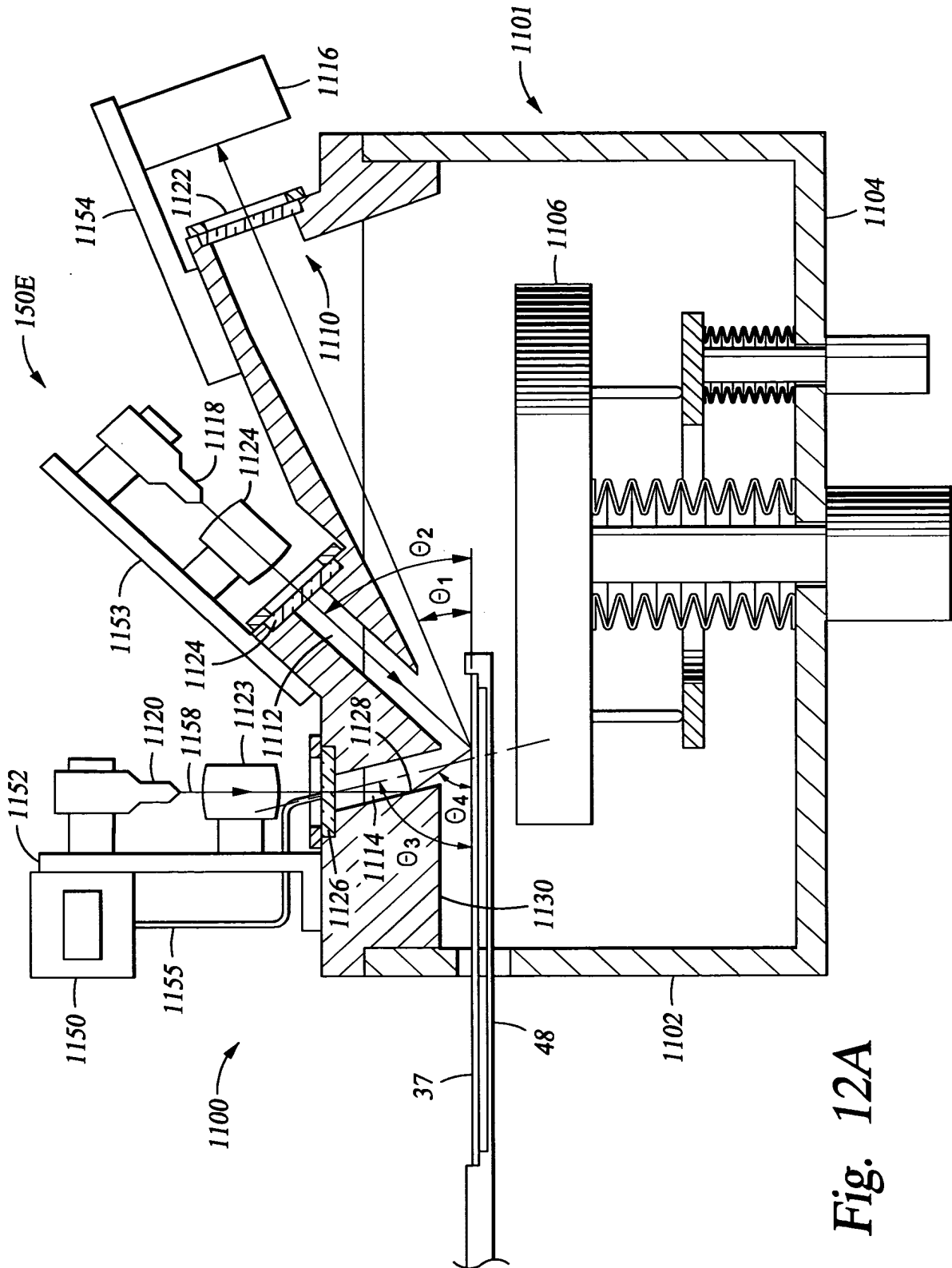
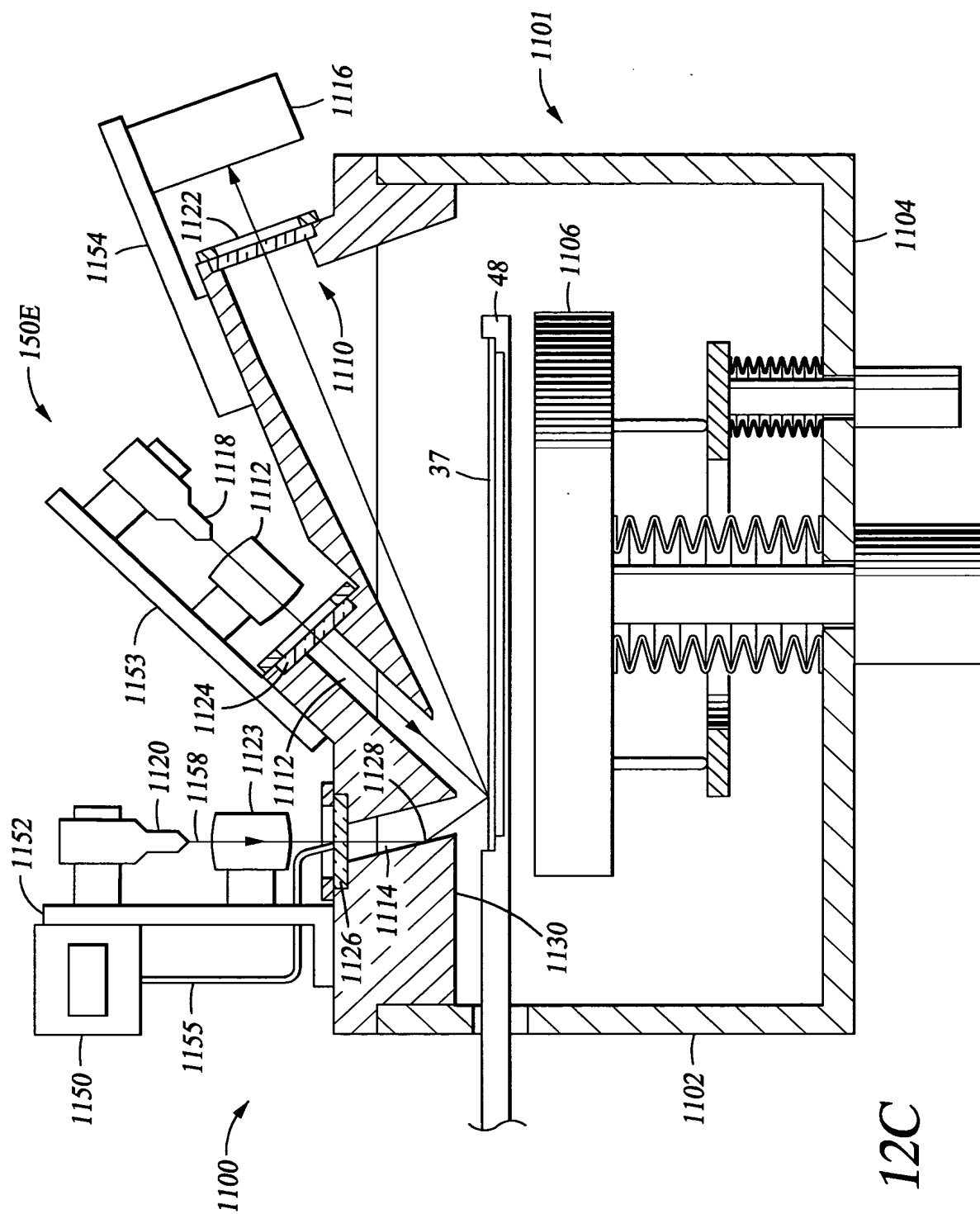


Fig. 12A









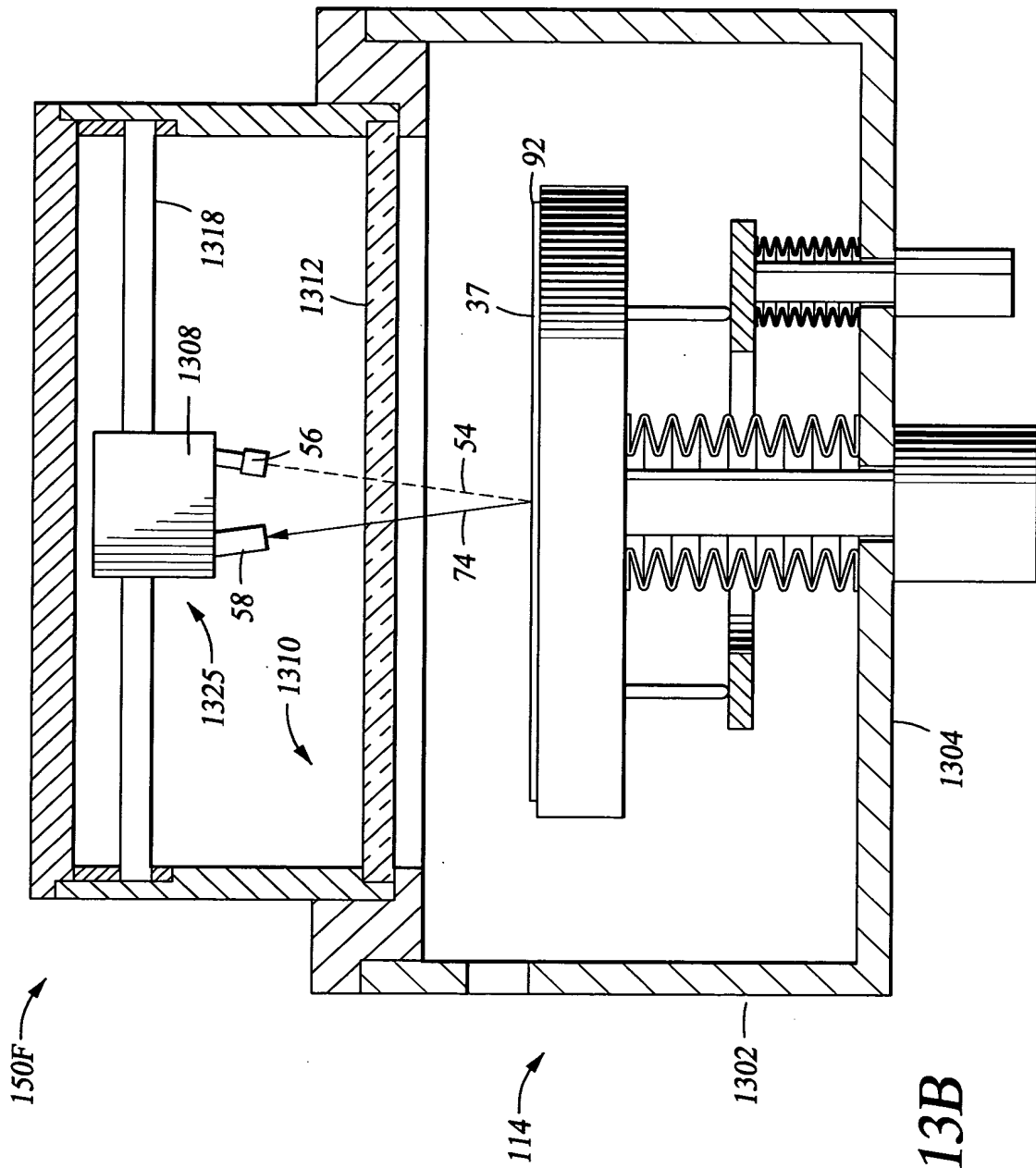


Fig. 13B



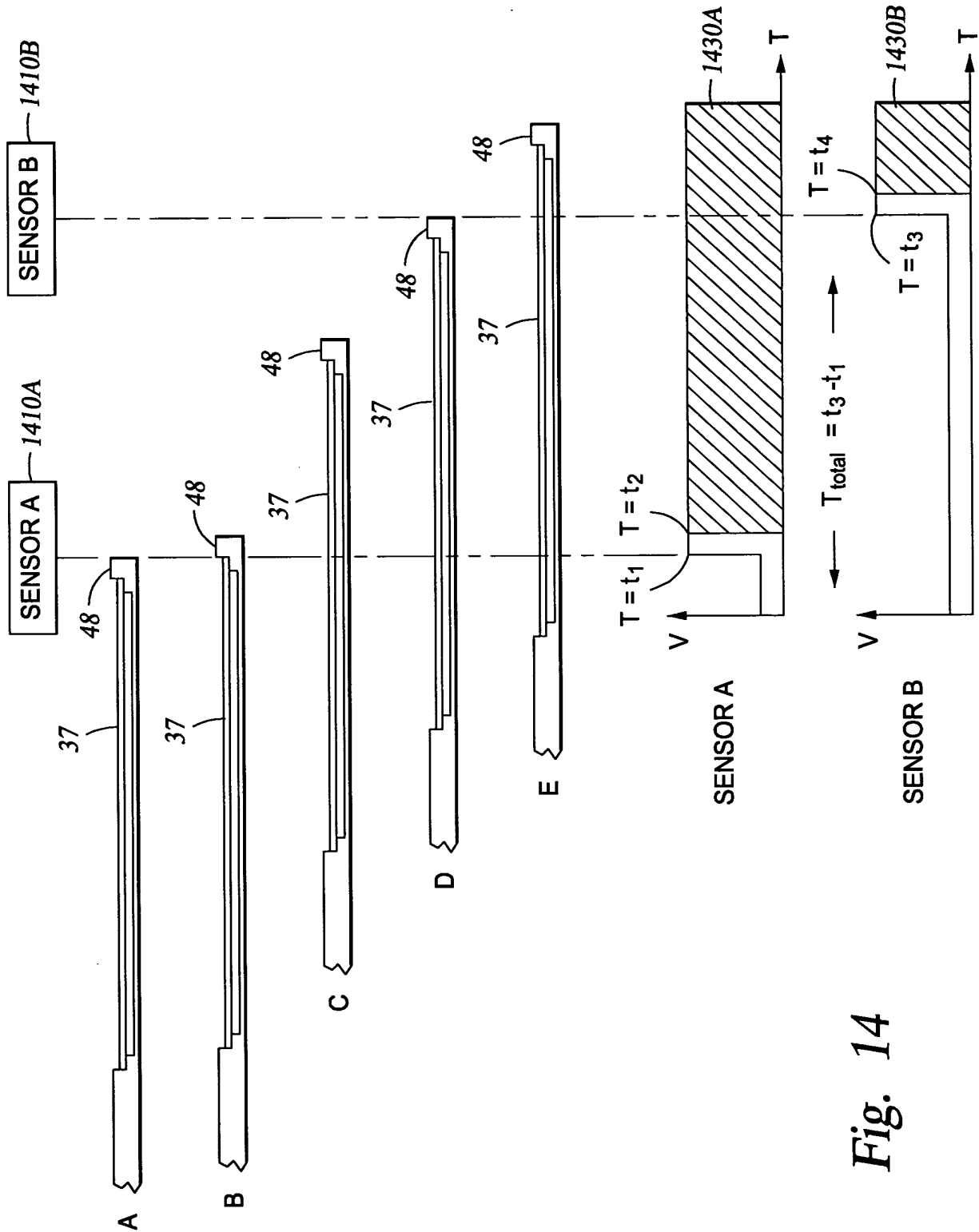
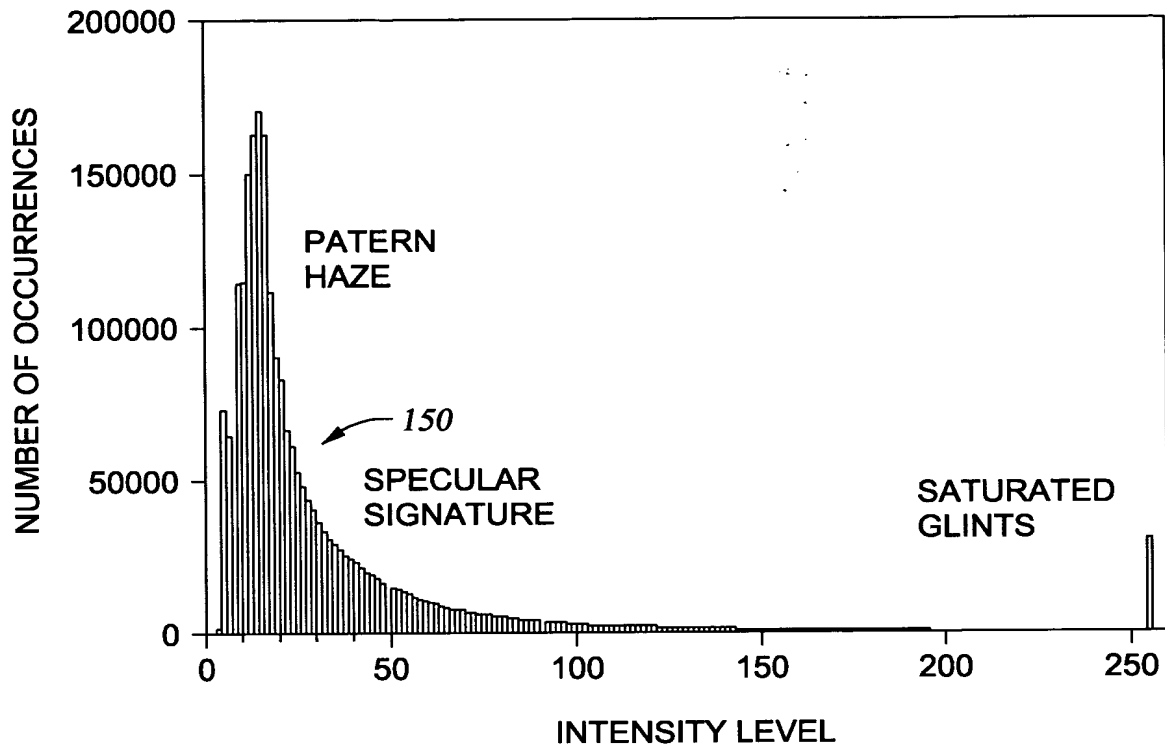
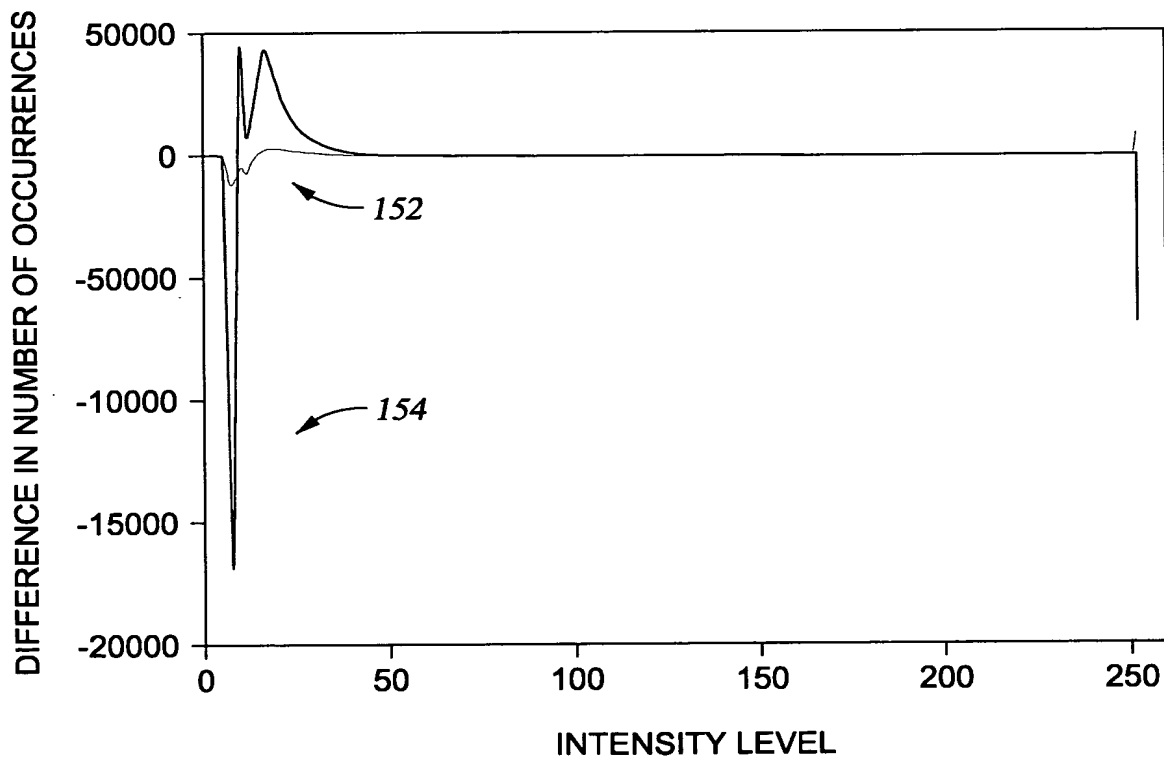


Fig. 14

*Fig. 15**Fig. 16*

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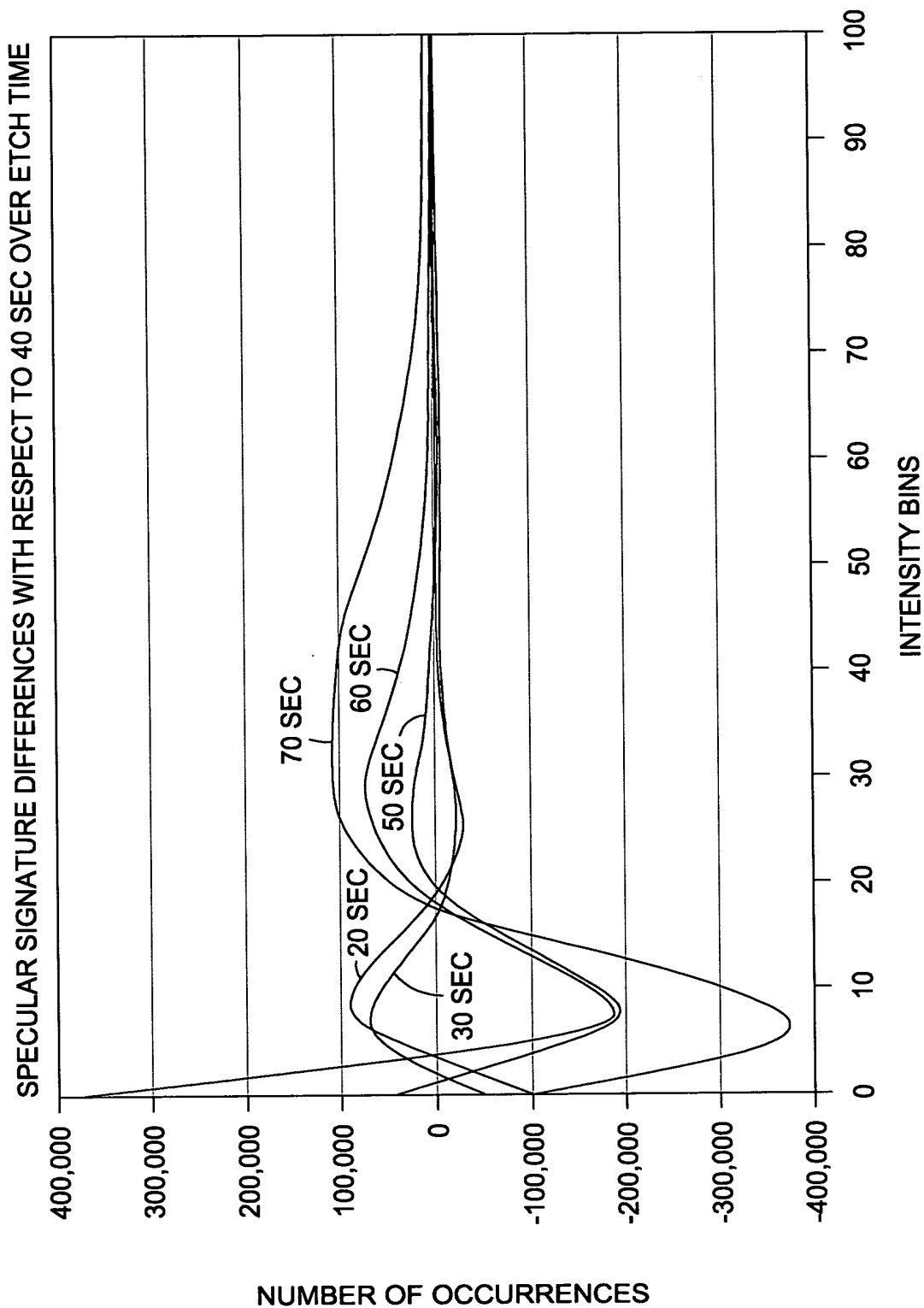


Fig. 17

TRADITIONAL ETCH ENDPOINT PLOT BASED ON CHANGES OF PROCES PLASMA

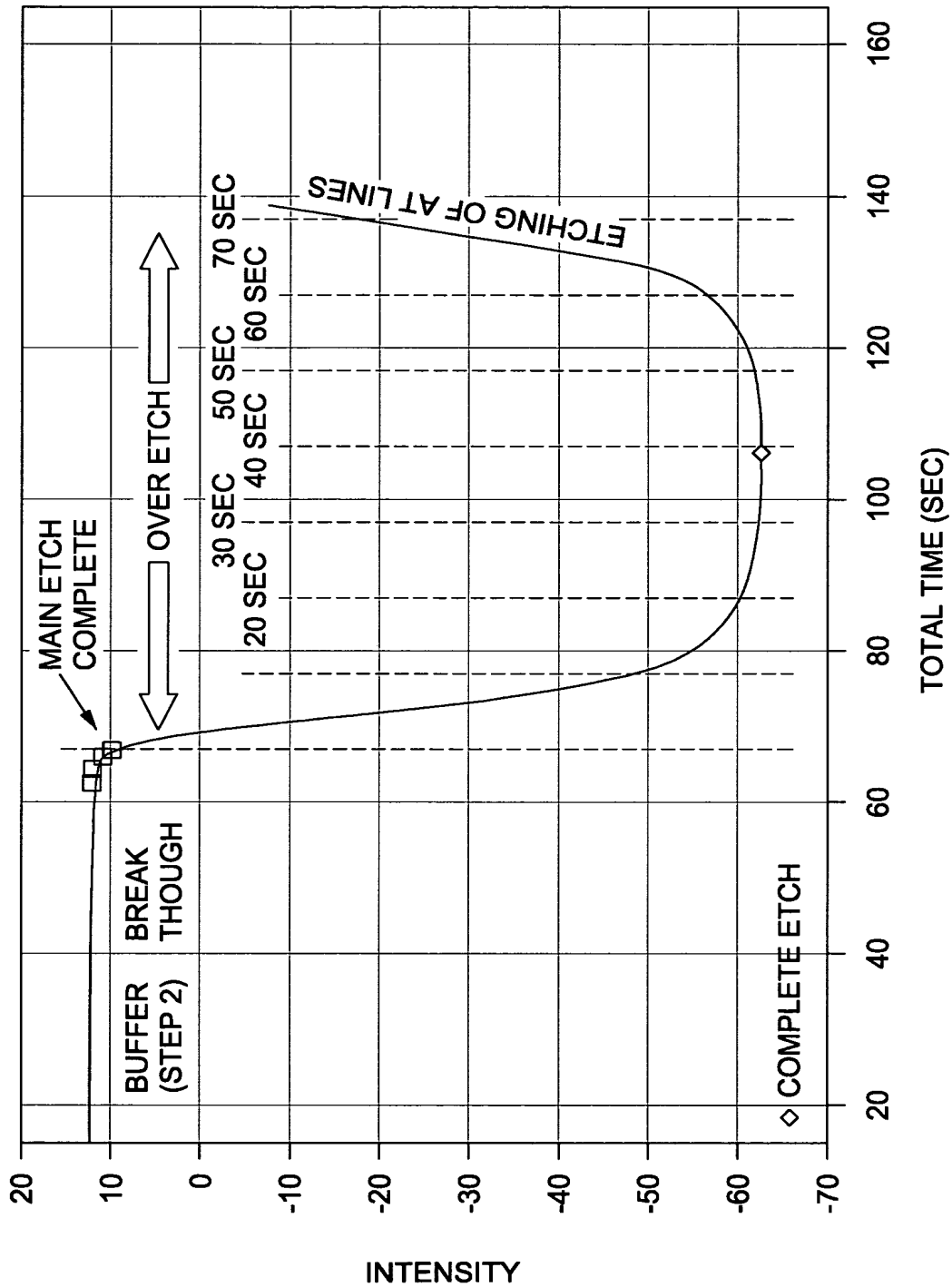


Fig. 18

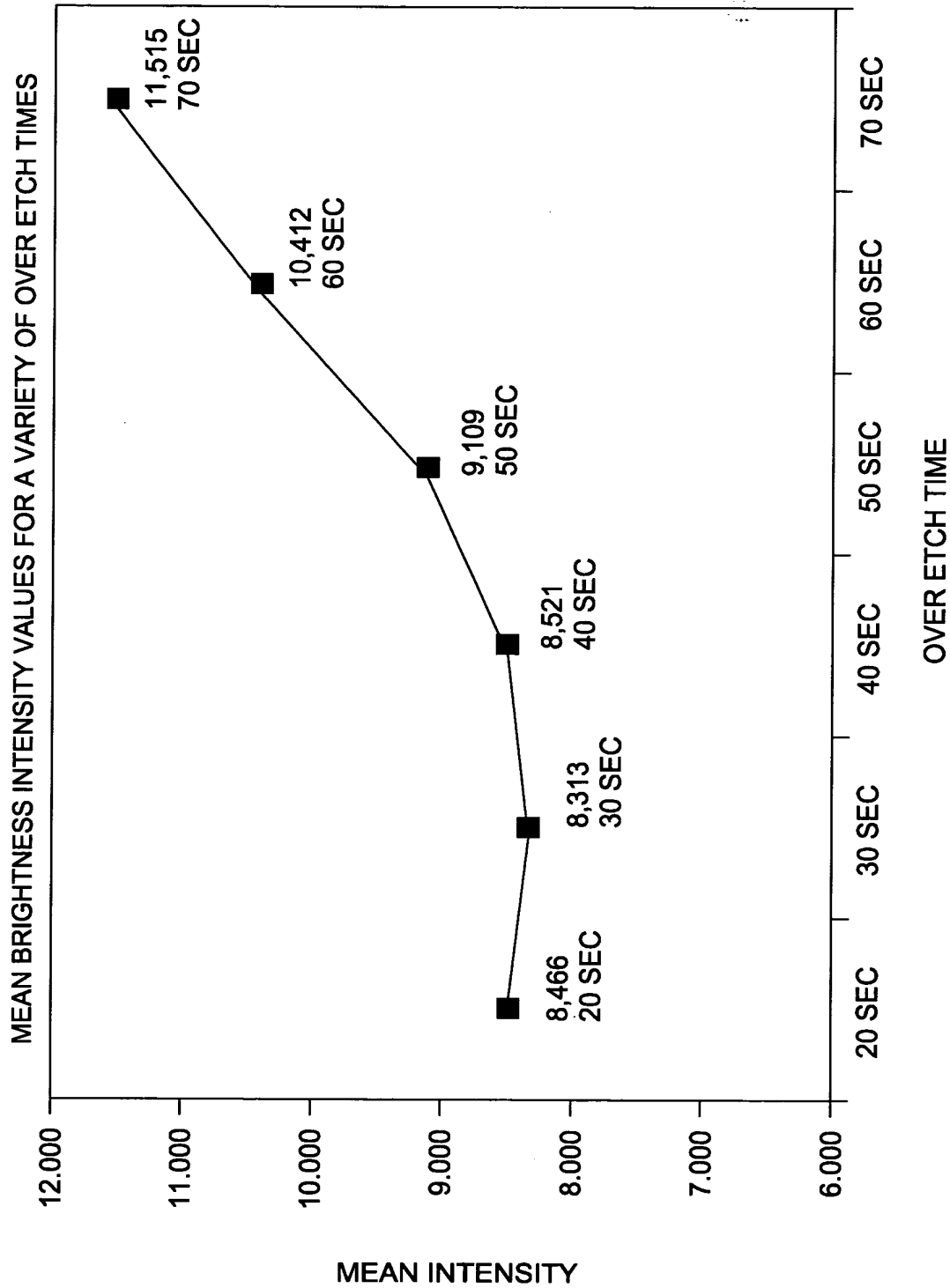


Fig. 19



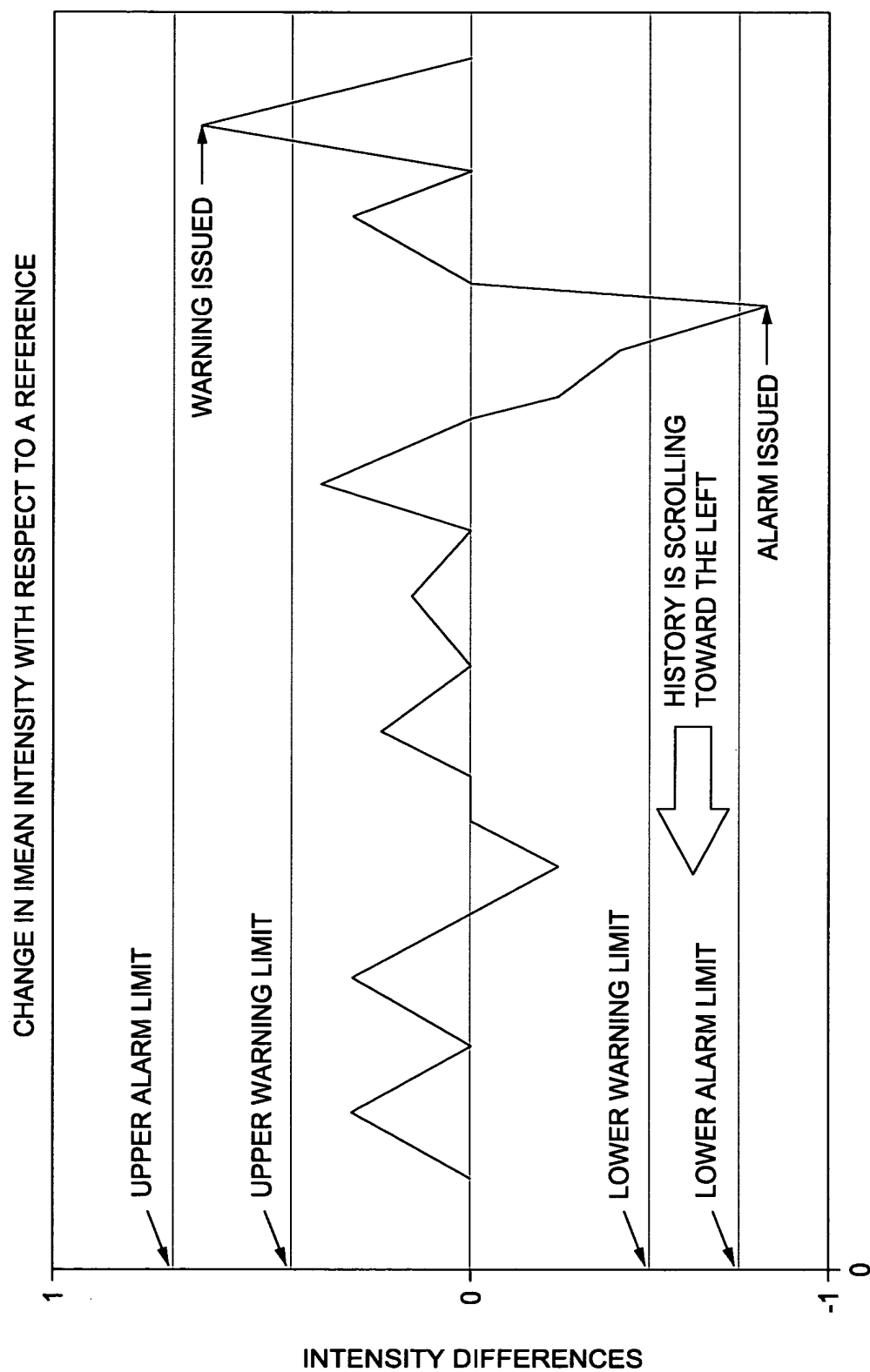


Fig. 20

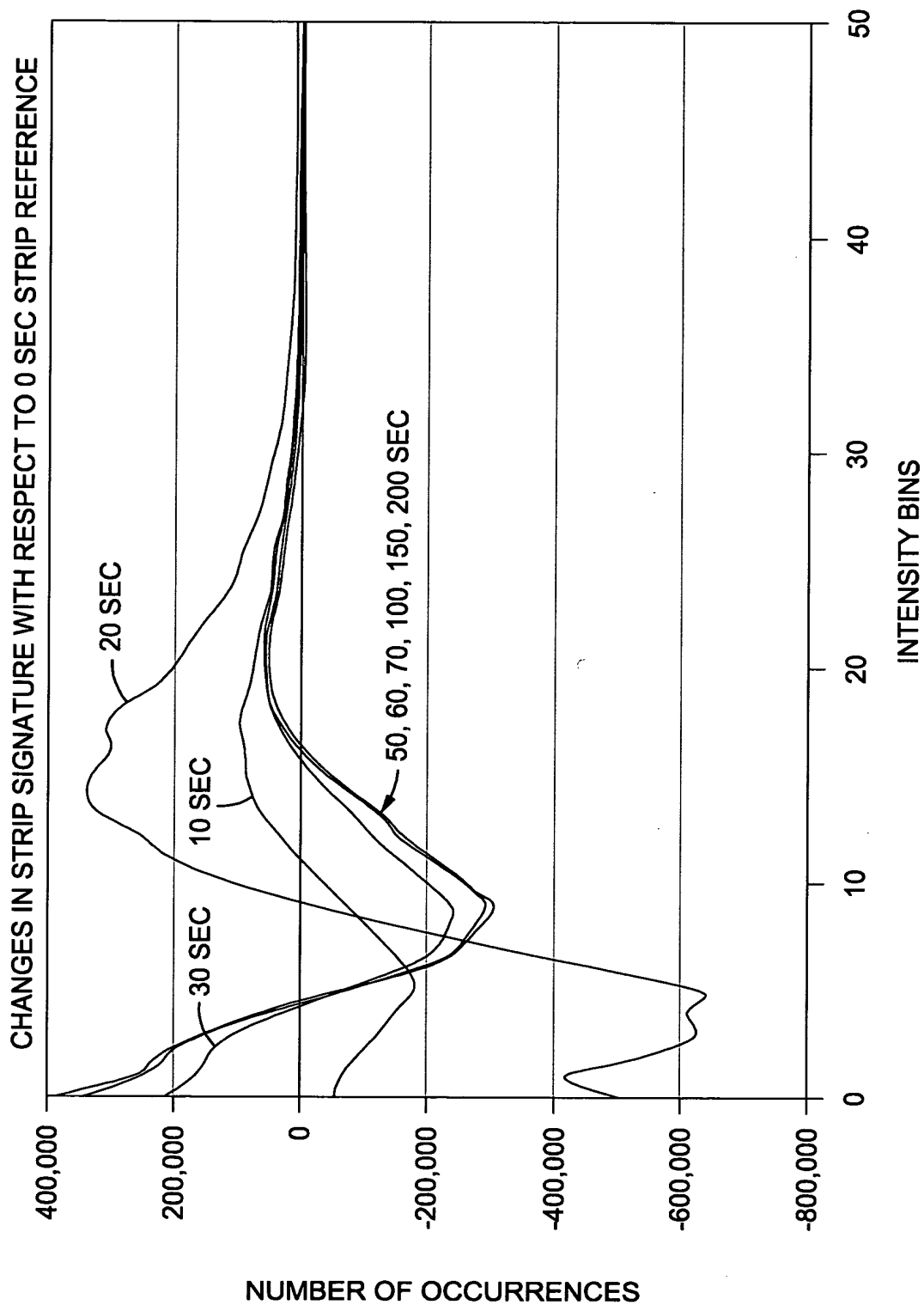


Fig. 21

DIFFERENCES IN STRIP SIGNATURES FOR STRIP TIMES LESS THAN 50 SECONDS WITH RESPECT TO AN OPTIMUM REFERENCE STRIP SIGNATURE

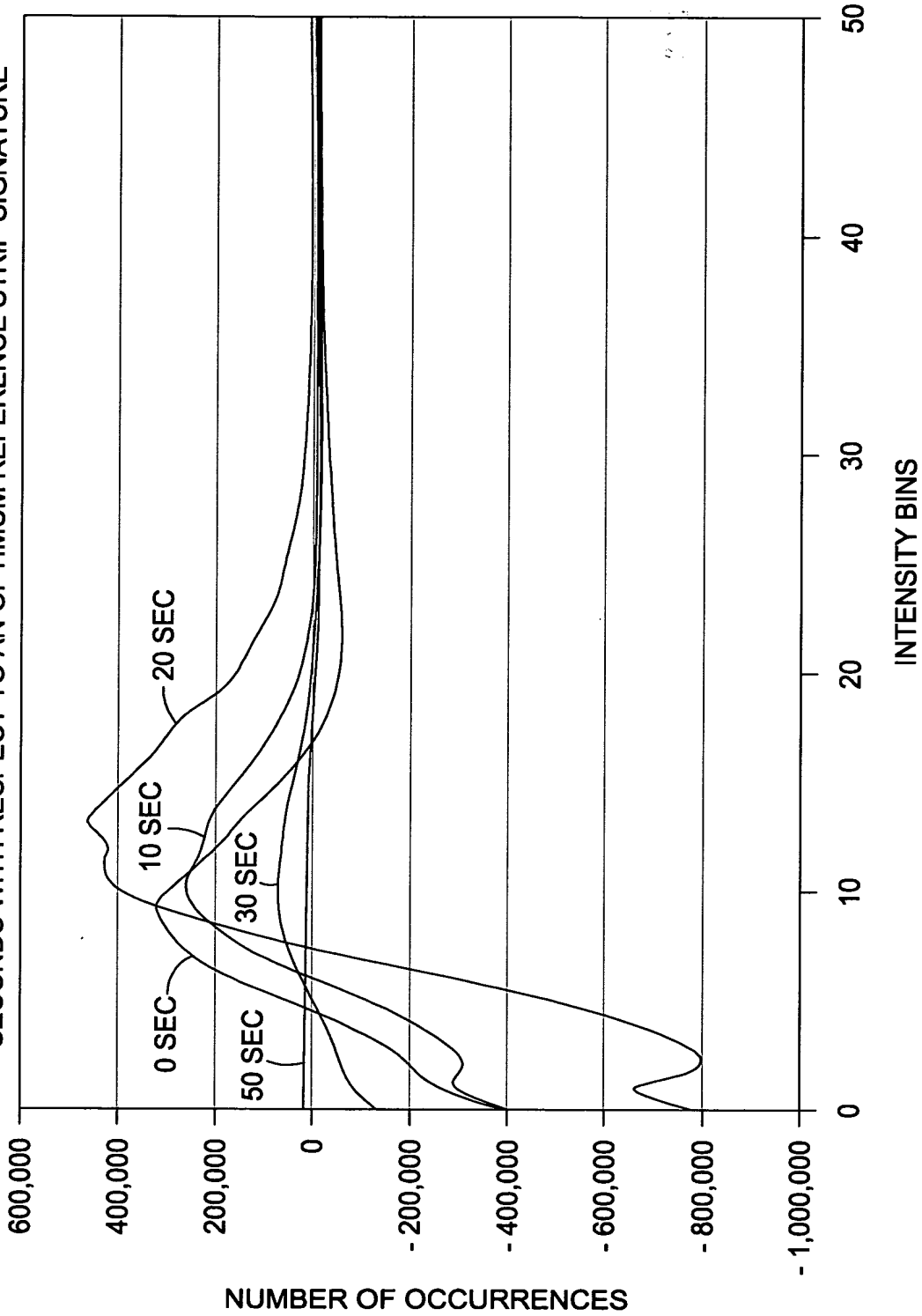


Fig. 22

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DIFFERENCES IN STRIP SIGNATURES FOR STRIP TIMES EXCEEDING 50  
SECONDS WITH RESPECT TO AN OPTIMUM REFERENCE STRIP SIGNATURE

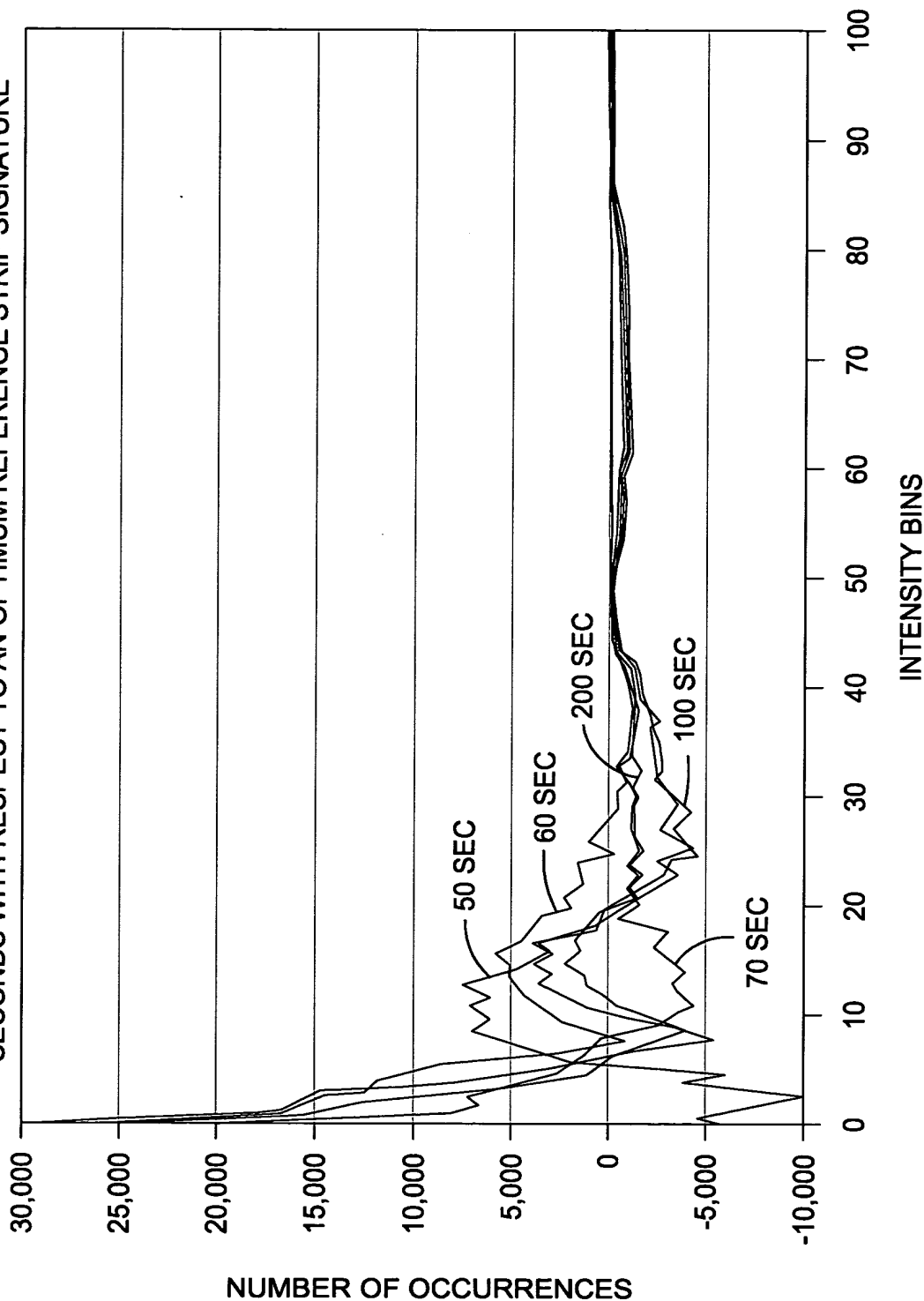


Fig. 23

SYSTEM GENERATED SCAN TO SCAN VARIANCES OF AN OPTIMALLY STRIPPED SUBSTRATE

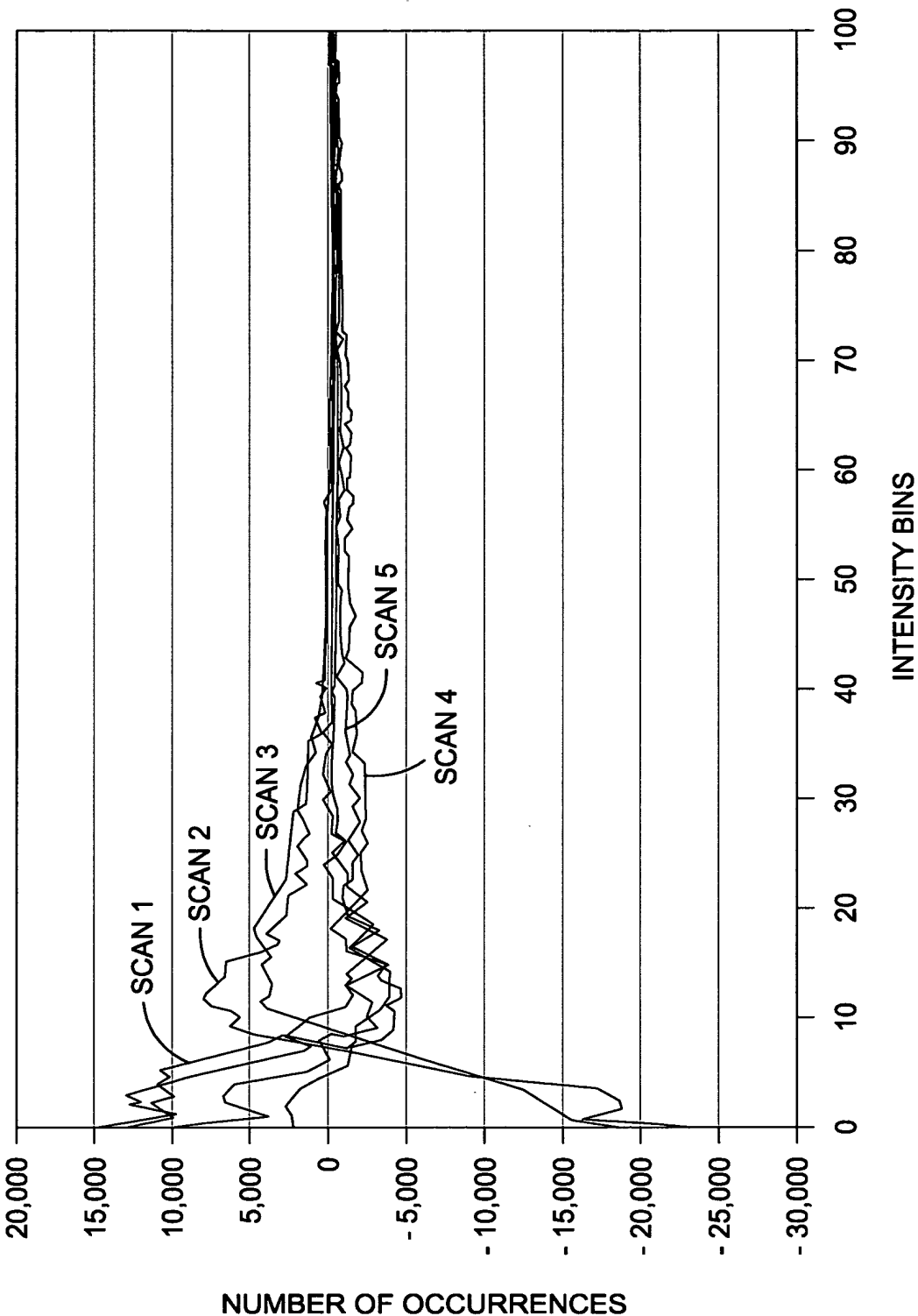


Fig. 24

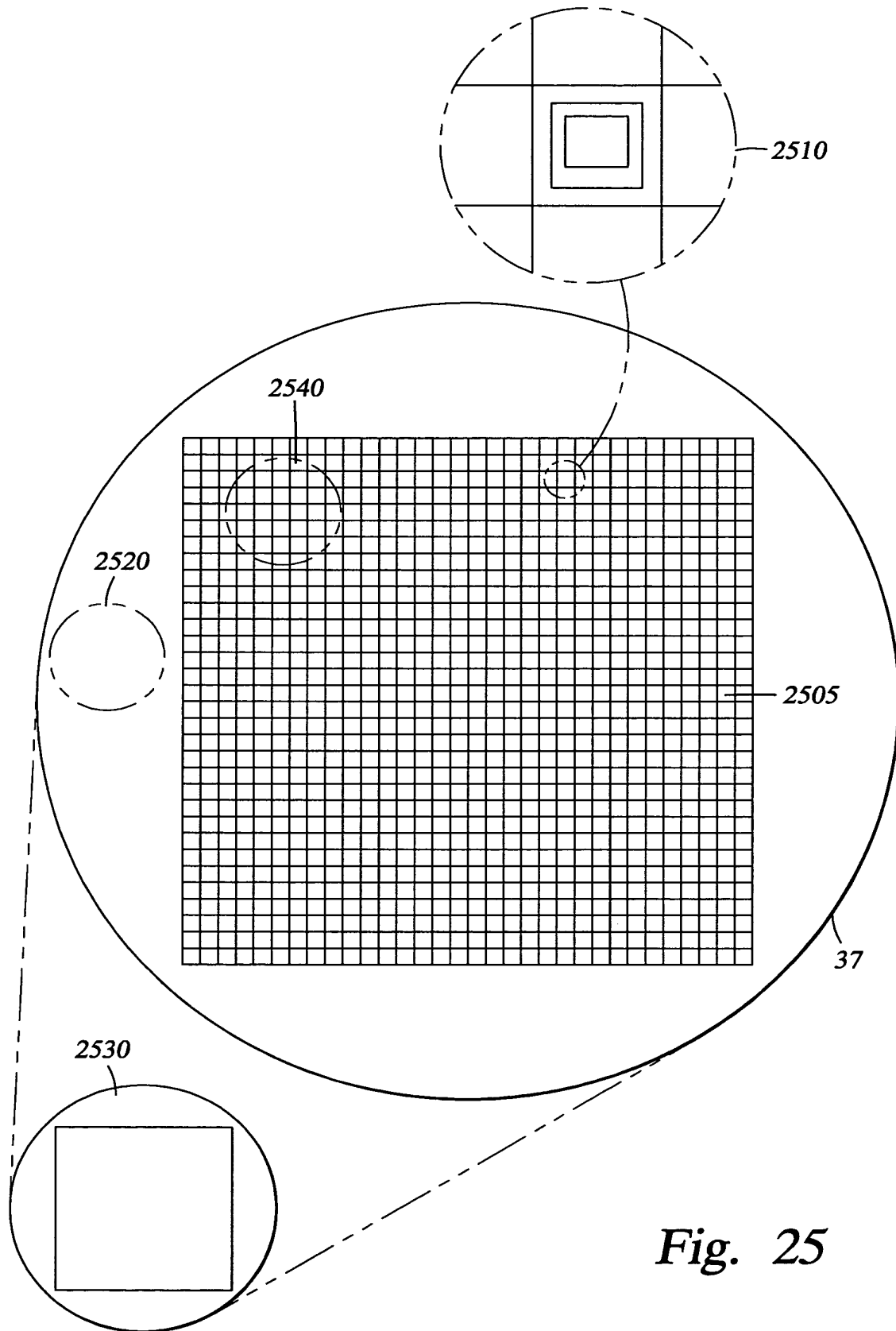


Fig. 25

09685191.1.00600

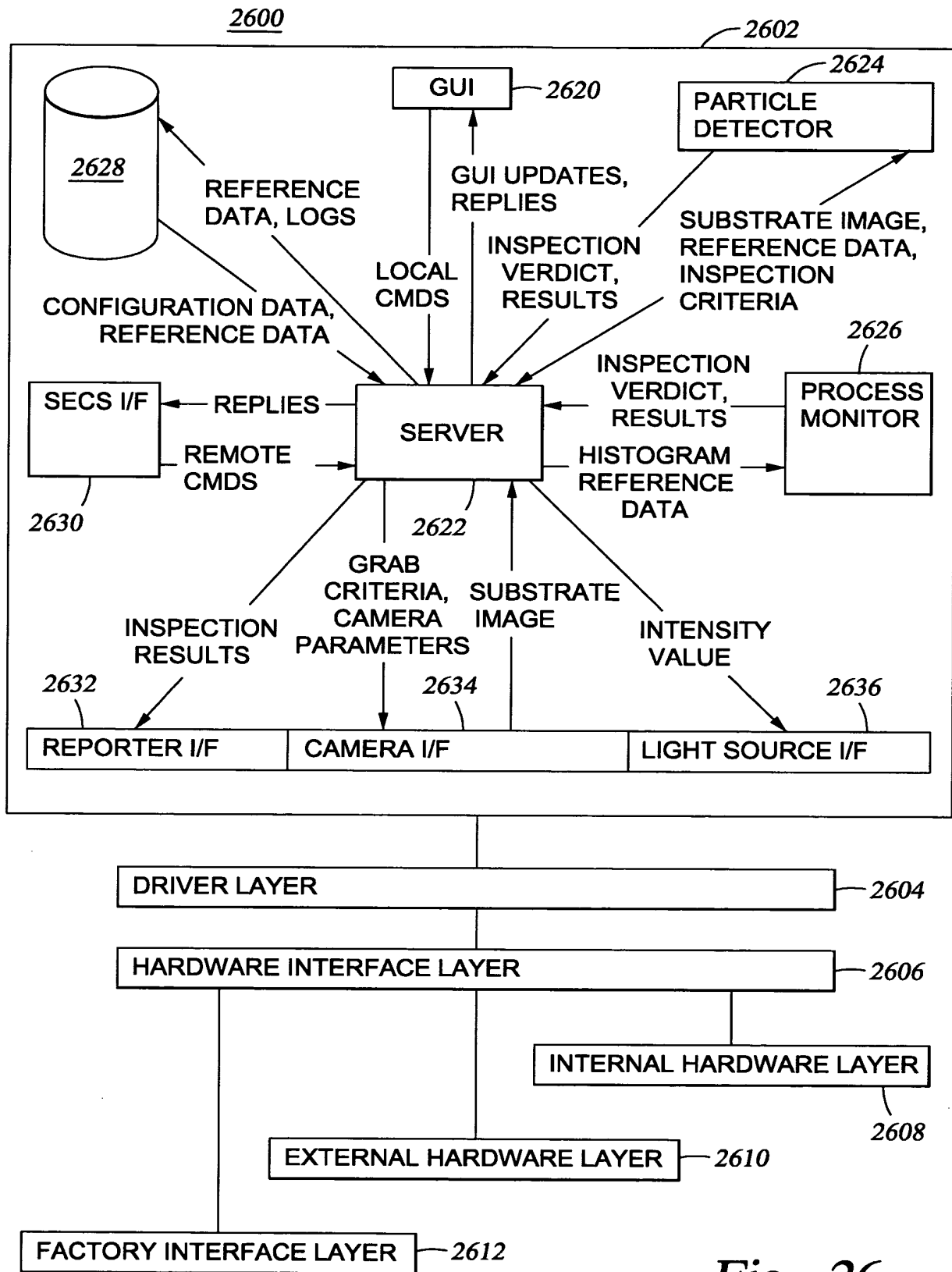


Fig. 26

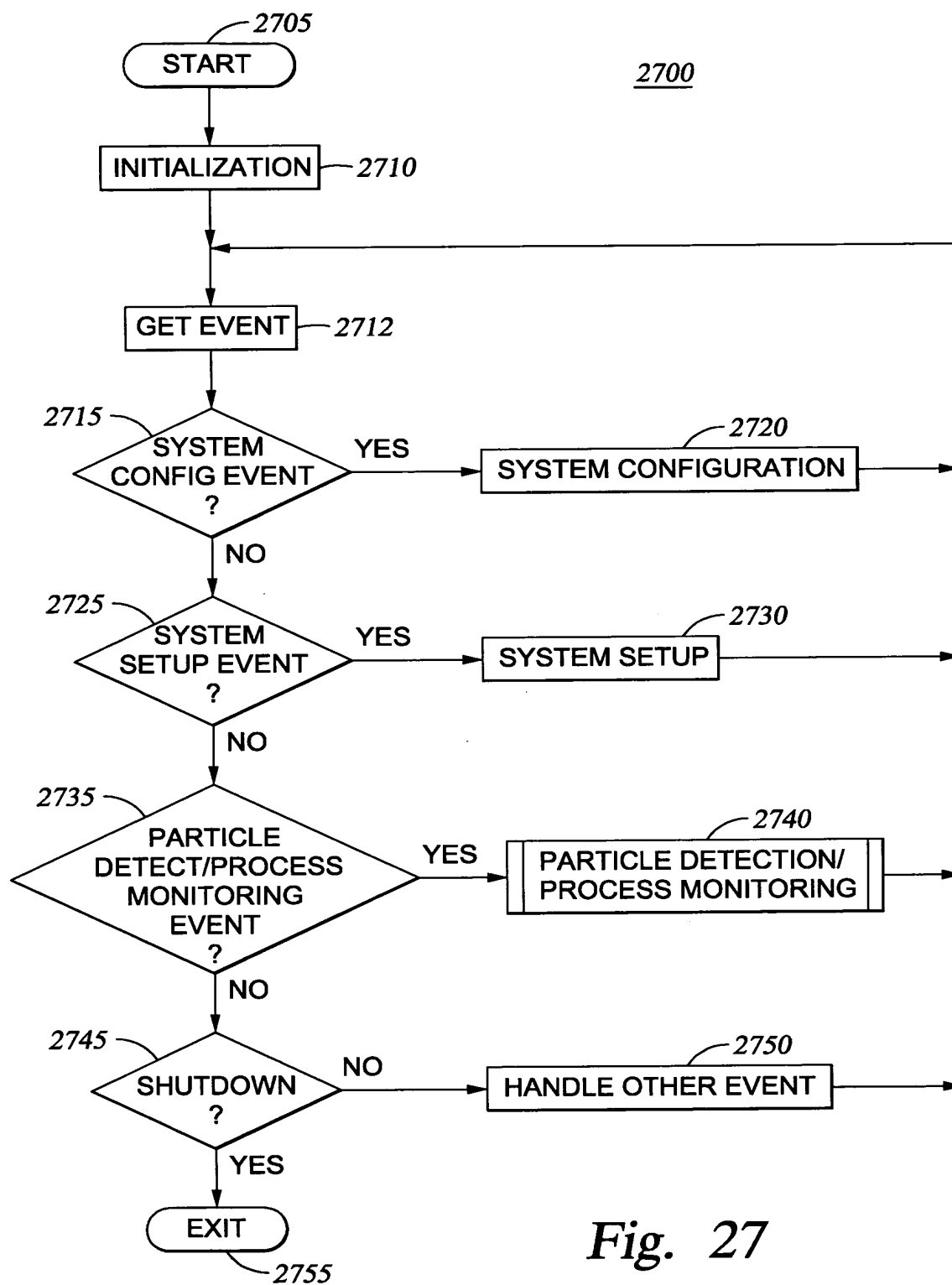


Fig. 27



Fig. 28

